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(54) **INDUCTIVE PROXIMITY SENSOR FOR DETECTING FERROMAGNETIC, NON-PERMEABLE OR
MAGNET TARGETS**

INDUKTIVER NÄHERUNGSSENSOR ZUR ERFASSUNG VON MAGNETEN,
FERROMAGNETISCHEN ODER PERMEABLEN ZIELEN

DETECTEUR DE PROXIMITE A INDUCTION DETECTANT DES CIBLES FERROMAGNETIQUES,
NON PERMEABLES OU MAGNETIQUES

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Description

Field of the Invention

[0001] The present invention relates to a non-contact proximity sensor and, more particularly, a proximity sensor having an increased sensing range and capable of sensing magnetic, ferromagnetic, and conductive targets.

Background of the Invention

[0002] A proximity sensor is a device used to detect the presence of an object. The design of a proximity sensor can be based on a number of principles of operation, some examples include: variable reluctance, eddy current loss, saturated core, and Hall effect. Depending on the principle of operation, each type of sensor will have different performance levels for sensing different types of objects. In particular, saturated core and Hall effect sensors are primarily used to detect the presence of magnetic objects, while variable reluctance and eddy current loss sensors are primarily used to detect the presence of metal objects.

[0003] Saturated core sensors are known in the prior art. Such proximity sensors typically include a core made from a material that will magnetically saturate when exposed to a magnetic field of a certain flux density. As a magnetic object is moved toward the core assembly, a distance is reached where the magnetic field of the object finds the core to be the smallest reluctance path. As a result, the flux of the field enters the core and, as the distance is decreased the flux density increases and eventually saturates the core. The saturation of the core causes the impedance of the coil to decrease. By measuring changes in the impedance of the coil, the presence of the magnetic object may be detected.

[0004] One example of a saturated core sensor can be found in U.S. Patent No. 4,719,362 to Nest et al. ("the Nest Patent"). The Nest patent discloses an inductive proximity sensor having a core, a conductive coil, and an oscillator circuit. The core is made from a metal that magnetically saturates when exposed to the magnetic field of a target.

[0005] Variable reluctance sensors are also known in the prior art. Such proximity sensors typically include a U-type core and coils wound around the core legs. Other typical shapes of variable reluctance proximity sensors cores include: Pot cores, pins, T-cores, E-cores and plates. These devices also typically include an electronic drive device for producing an oscillating electromagnetic field around the coil. Square waves, sine waves, trapezoidal waves, and other unique wave shapes have been used to interface to these sensors. As a permeable object is moved toward the variable reluctance proximity sensor, the permeable object reduces the reluctance of the electromagnetic system, and this variation in the reluctance is measured as a change in the inductance and

AC resistance of the coil. When the permeable object moves toward a variable reluctance sensor, the inductance and AC losses of the coil increase.

[0006] In some designs, two coils are used, one to produce the electromagnetic field and another to measure the variations in the reluctance. In conventional variable reluctance proximity sensors, it has been common practice to use a ferrite core. The sensing coils are placed on the core to optimize the magnetic field extending to the target material. The core is shaped to contain and extend the electromagnetic field surrounding the coil in a sensing direction or to concentrate or channel the field in other directions, such as behind and to the sides of the coil. One example of a variable reluctance sensor is shown in U.S. Patent No. 4,387,339 to Akerblom ("the Akerblom patent"). The Akerblom patent discloses an apparatus for measuring the distance between two moving objects.

[0007] Eddy current sensors are also known in the prior art. Such proximity sensors have a similar design to variable reluctance sensors in that they typically include Pot cores or U-type core, a coil wound around the center post of the core or the core legs, and an oscillator for producing an oscillating electromagnetic field around the coil. As with the variable reluctance proximity sensor, the eddy current sensor detects the presence of a conducting object by measuring the real and imaginary AC losses of the coil; however, in this design, if the target material is only conductive, the inductance of the coil decreases as the object is moved toward the target.

Summary of the Invention

[0008] The present invention provides a proximity sensor that operates as a saturable core proximity sensor, a variable reluctance proximity sensor, and an eddy current proximity sensor. In the preferred embodiment, the core is made of a highly permeable metal. The preferred embodiment provides a durable, low cost, lightweight proximity sensor with increased sensitivity and additional manufacturing benefits.

[0009] The precision shaped metal core and the supporting assembly are designed to optimize the sensitivity of the device in three modes of operation. In one mode of operation, the proximity sensor is used to detect the presence of a magnet. When the magnet approaches the sensor, the unique shape and dimensions of the core allow for easy saturation of the core in the magnetic field. When the magnet is close to the sensing device, the core saturates and significantly changes the impedance of a coil configured around the core. A first sensing circuit connected to the coil is used to detect variations in the impedance and configured to provide a signal to indicate the presence of a magnetic object when the coil impedance fluctuates.

[0010] In a second mode of operation, the proximity sensor is used to detect the presence of ferromagnetic metals objects, also referred to as permeable metals. In

this mode, the coils around the core provide a source field and also provide a means for measuring variations in source field. When a permeable object moves into the source field, the inductance of the coil increases. A second sensing circuit connected to the coil is used to detect variations in the inductance of the coil and configured to provide a signal to indicate the presence of a ferromagnetic target when the coil inductance fluctuates. The highly permeable steel sensor core provides a design with increased sensitivity for detecting ferromagnetic objects at increased ranges.

[0011] In a third mode of operation, the proximity sensor is used to detect the presence of conductive objects, such as copper or aluminum. In this mode, the inductance of the coil decreases when a conductive object moves into the source field. The second sensing circuit connected to detect variations in the inductance of the coil. Similar to the variable reluctance mode, when a permeable object moves into the source field, the inductance of the coil increases. A second sensing circuit connected to the coil is used to detect variations in the inductance of the coil and configured to provide a signal to indicate the presence of a ferromagnetic target when the coil inductance fluctuates. The highly permeable steel sensor core also provides a design with increased sensitivity for detecting conductive objects at increased ranges.

[0012] A specific core design that can be used in the present invention is a thin, highly permeable metal that is preferably formed from a single piece of sheet metal. The core comprises a substantially flat, rectangular member bent in four locations to form a shape that resembles a rectangular Greek omega character having a head, two legs, and two feet. The bends are right angles with 60 degree bend radii so that the head is perpendicular to the two legs, and the two legs are perpendicular to the two feet. The two feet are parallel to each other, occupy a common plain and also parallel to the head.

[0013] The core is positioned in a housing with two inductive coils, each coil being positioned around one of the feet of the core. Another embodiment of the present invention also provides a core and coil assembly with a calibration bolt that is placed through the center of the core to adjust the inductance range of the proximity sensor.

[0014] The thin metal structure of the core also provides many other benefits in the manufacturing process of the proximity sensor. Specifically, the thin metal core allows for a more efficient manufacturing process that does not require a considerable amount of machine work, as compared to the prior art U-type metal cores. The core design also provides a rugged, lightweight structure that is not susceptible to great temperature fluctuations. Another advantage of the present invention is that it can be used as a permeable metal target sensor, an eddy-current-loss sensor, or a magnetic field sensor without the need of special preparations to

switch the detectors for different types of applications. The proximity sensors of the present invention also provide a core design with increased sensitivity while having a design that is produced in a sufficiently small size.

Brief Description of the Drawings

[0015] The foregoing aspects and many of the attendant advantages of this invention will become more readily appreciated as the same become better understood by reference to the following detailed description, when taken in conjunction with the accompanying drawings, wherein:

FIGURE 1 is a top front perspective of one embodiment of a proximity sensor utilizing an omega core in accordance with the present invention;

FIGURE 2 is a section along line 2--2 of FIGURE 1; FIGURE 3 is a top rear perspective of the proximity sensor of FIGURE 1, with parts shown in exploded relationship;

FIGURE 4A is an enlarged perspective of the core used in the proximity sensor of FIGURES 1-3; FIGURE 4B is a side elevation of FIGURE 4A; FIGURE 4C is an end elevation thereof; FIGURE 4D is a bottom plan thereof; FIGURE 4E is a longitudinal vertical section thereof;

FIGURE 5 is a section corresponding to FIGURE 2, but showing another embodiment of a proximity sensor in accordance with the present invention;

FIGURE 6A is an enlarged perspective of the core used in the proximity sensor of FIGURE 5; FIGURE 6B is a side elevation of FIGURE 6A; FIGURE 6C is an end elevation thereof; FIGURE 6D is a bottom plan thereof;

FIGURE 7 is a somewhat diagrammatic top plan of a proximity sensor in accordance with the present invention adjacent to a magnetic target;

FIGURE 8 is a graph of the impedance of the sensor coils as a function of the distance between the magnetic target and the proximity sensor of FIGURE 6;

FIGURE 9 is a somewhat diagrammatic top plan of a proximity sensor in accordance with the present invention adjacent to a permeable target;

FIGURE 10 is a graph showing the sensitivity of the sensor coils versus the distance between the permeable target as the proximity sensor is used in the variable reluctance mode;

FIGURE 11 is a graph showing the sensitivity of the sensor coils versus the distance between the permeable target as the proximity sensor is used in the eddy current loss mode;

FIGURE 12 is a side view of another embodiment of a proximity sensor utilizing a cup core in accordance with the present invention;

FIGURE 13A is a section along line 13A--13A of FIGURE 12, FIGURE 13B is a top rear perspective of the proximity sensor of FIGURE 12 with parts

shown in exploded relationship;

FIGURE 14A is a side elevation of the core used in the proximity sensor of FIGURE 12; FIGURE 14B is a section along line 14B--14B of FIGURE 14A; FIGURE 15A is an axial section of yet another embodiment of a proximity sensor utilizing a cup core in accordance with the present invention; and FIGURE 15B is a top front perspective of the embodiment of a proximity sensor of FIGURE 15A with parts shown in exploded relationship;

FIGURE 16 is a diagrammatic side elevation of a proximity sensor in accordance with the present invention adjacent to a magnetic target with parts broken away;

FIGURE 17 is a graph of the impedance of the sensor coils as a function of the distance between the magnetic target and the proximity sensor of FIGURE 16;

FIGURE 18 is a diagrammatic side elevation of a proximity sensor in accordance with the present invention adjacent to a permeable target with parts broken away; and

FIGURE 19 is a graph showing the sensitivity of the sensor coils of a proximity sensor versus the distance between the permeable target as the proximity sensor is used in the variable reluctance mode.

Detailed Description of the Preferred Embodiment

[0016] While advances have been made in the design of proximity sensors to improve their range and sensitivity, improvements of the various proximity sensors have not focused on providing a proximity sensing device that operates efficiently under different principles of operation. More specifically, prior art proximity sensors that have been developed to operate as a variable reluctance sensor do not operate efficiently as a saturated core sensor. Accordingly, prior art proximity sensors that have been designed to operate as a saturated core sensor do not operate well as a variable reluctance sensor. The present invention provides a core design that is able to operate under both principles of operation and provide a core design that also operates as an eddy current loss sensor. The present invention provides a highly sensitive, low cost, rugged core design that can operate under different principles of operation and that can detect multiple classes of target materials. In particular, the present invention provides a proximity sensor that is of a relatively straightforward structure that makes use of elements common to existing sensors, and adapted to accommodate magnetic and non-magnetic metal objects.

[0017] In addition, the present invention provides a core design with an extended sensing field without the need of a ferrite material or machined metal core. Proximity sensors that use ferrite cores have a degradation in their performance due to fluctuations in operating temperatures, age and particular material properties,

such as brittleness and variance in initial material conditions. Other proximity sensors using a machined metal or metal laminated cores have been used in the art; however, these core designs are typically more difficult and more expensive to manufacture. The core design of the present invention using a thin permeable material provides increased performance as well as providing other manufacturing benefits.

[0018] The present invention provides a proximity sensor that operates as a saturable core proximity sensor, a variable reluctance sensor, and an eddy current loss sensor. In one mode of operation, the proximity sensor is used to detect the presence of a magnet. In another mode of operation, the proximity sensor is used to detect ferromagnetic objects or permeable targets. In yet another mode of operation, the proximity sensor is used to detect conductive targets such as copper or aluminum, along with any combination thereof. Target material recognition, and combining materials in a target are common methods of improving discriminating functions. The structure and methods of different embodiments of the present invention will become more readily apparent from the following detailed description, when taken in conjunction with the accompanying drawings.

[0019] With reference to FIGURES 1 and 2, a first embodiment of a proximity sensor 100 in accordance with the present invention includes a housing 102 having a target-facing front surface 104 and four sidewalls 106 extending at right angles from surface 104. The sidewalls 106 and front surface 104 form a hollow interior region in the housing 102. As shown diagrammatically in broken lines in FIGURE 1, a sensing region 200 extends out from the target-facing front surface 104 in a generally hemispherical shape. For example, in a representative embodiment, the proximity sensor 100 can have an effective sensing range of approximately 0.8 inches in the Y direction (around to the front 104) and an effective range diameter of approximately 1.5 inches in the X-Z plane (parallel to the surface 104). The proximity sensor 100 in FIGURE 1 is effective for detecting magnetic, permeable, and non-permeable conductive metallic targets in the sensing region 200.

[0020] The housing 102 includes two flanges 108 extending outward from the opposite sidewalls 106. The flanges 108 have apertures 110 to permit the proximity sensor 100 to be mounted on a support member by the use of bolts or screws, such as on a frame or sash for a closure member. The housing 102 is preferably made from a durable, non-magnetic material having a fairly low electrical conductivity, i.e., a conductivity level approximate to titanium. It is preferred that a physically strong, low conductivity, non-corrosive and non-magnetic material, like titanium or stainless steel be used in the construction of housing 102. However, to maximize the performance of the proximity sensor, other nonconducting materials such as formable plastics can be used to construct the housing 102. The performance of the sensor increases as the conductivity of the housing 102

decreases. The use of a highly conductive material should be avoided because eddy currents may form on the housing surface and reduce the effective range 200 of the proximity sensor 100. In addition, the use of ferromagnetic materials should be avoided because the housing 102 may contain the sensing field produced by the proximity sensor 100.

[0021] The housing 102 also includes a rear opening to the hollow interior for the insertion of the internal components. Referring now to FIGURE 3, the proximity sensor 100 is assembled by sliding the two insulators 116 into the opening of the housing 102. The two insulators 116 are preferably constructed from a non-conductive material such as plastic or Mylar with a thickness approximate to three Mils. The two insulators 116 may be molded in a cup shaped form to provide an insulating shield between two coil assemblies 118 and the housing 102.

[0022] The two coil assemblies 118 are then inserted into the two insulators 116. The two coil assemblies 118 comprise a plurality of turns of a relatively fine copper wire with a preferred gauge of thirty-seven. Although a gauge of thirty-seven is preferred, the two coil assemblies 118 may be constructed from any insulated wire material with a gauge range from twenty-six to fifty. From a view looking into the opening of the housing 102, the coil assemblies are formed by turning the wire of one coil in a clockwise direction and by turning the wire of the second coil in a counterclockwise direction. Either coil may have the wire turn in the clockwise direction so long as the wire in the other coil is turned in the opposite direction. One wire from one coil should be connected to one wire from the other coil to create a closed loop circuit between the two coils. The other two open ends of each coil are connected to electrical contacts in an external connector 140.

[0023] The closed loop circuit formed by the coil wires is connected to a circuit 101 external to the housing 102. Two different circuits can be connected to the two coil assemblies 118 through the external connector 140 to accommodate three modes of operation. For the saturated core mode of operation, the closed circuit created between the two coil assemblies is connected to a circuit that has the capability of measuring the impedance of the two coils. This arrangement allows the proximity sensor 100 to detect the presence of magnetic targets. The impedance measuring circuit used in this configuration can be similar to a circuit that is commonly used in the art to measure impedance, such as an impedance meter.

[0024] In the other two modes of operation, the closed loop circuit created between the two coil assemblies is connected to a circuit having the capability to detect inductance of the two coils and to provide an alternating current to the two coils. This arrangement allows the proximity sensor 100 to detect the presence of permeable and conductive objects by sensing variations in the inductance of the two coils. The inductance measuring

circuits used in these configurations are similar to those circuits that are commonly used in the art to operate common variable reluctance and eddy current loss proximity sensors, or again, an impedance meter.

[0025] The two coil assemblies 118 are also suitably formed in a rectangular configuration to accommodate the insertion of the core's foot portions. As described below, one embodiment of the core 120 has foot portions having a width of 0.292 inches and a length of 0.275 inches, thus the core should have a center opening of approximately 0.302 by 0.285 inches. The height of the coil in this embodiment should be approximately 0.250 inches.

[0026] After the two coil assemblies 118 are inserted, the core 120 is placed into the housing 102, such that the legs of the core 120 fit tightly into the openings of the two coil assemblies 118. FIGURES 4A-4E illustrate various views of the core 120 to show the unique aspects of its design. The core 120 comprises a substantially flat, rectangular member bent in four locations to form a shape that resembles a rectangular Greek omega character having a head portion 220, two legs 222, and two foot portions (feet) 224. The bends are at right angles so that the head portion 220 is perpendicular to the two legs 222, and the two legs are perpendicular to the two feet 224. The two feet 224 are parallel to each other and coplanar, extend oppositely from the respective legs. Both feet portions 224 are also parallel to the head portion 220.

[0027] The head portion of the core 220 has a preferred width of 0.370 inches and a preferred length of 0.39 inches. The two legs 222 that extend at right angles from the head portion 220 have a preferred width of 0.292 inches and a preferred length of 0.300 inches. The two feet 224 extend away from each other and have a preferred length of 0.275 inches and preferred width of 0.292 inches. As illustrated in FIGURE 4B, if the omega shaped core is positioned to stand on the two feet 224, the core would have a height of 0.320 inches and a total length of 0.94 inches.

[0028] FIGURES 4A-4E also show that the top section of each of the two legs has a width equal to the width of the head portion 220, and the bottom section of each leg has a width that is more narrow than the width of the top section. The wider top section should extend down each leg approximately 0.050 inches. Accordingly, the narrow bottom section of the each leg should extend down the remaining portion of each leg having a length of approximately 0.250 inches.

[0029] FIGURE 4E is a side section of the core 120 illustrating the orientation of the above-described core 220 components. More specifically, FIGURE 4E illustrates that a section of the core comprises a head portion 220, two legs 222, and two foot portions (feet) 224. As shown in FIGURE 4E, the section of the core illustrates that the two legs 222 extend in a plane that is at a right angle from the plane created by the head portion 220. In addition, the two feet 224 extend away from each other

er and each foot creates a plane that is preferably parallel to one another and parallel to the plane created by the head portion 220.

[0030] The core 120 is preferably constructed from a highly permeable material such as soft iron, cast iron, transformer steel, or any other like material. The relative permeability should be at least 10,000. Although a relative permeability is suggested to be at least 10,000, higher values are desired to increase the sensor's performance. One material that is preferred is referred to in the art as HyMu "80"®, available from Carpenter Steel Company of New Jersey. It is also preferred to form the core from one piece of metal with a thickness of approximately 0.020 inches. Although this embodiment shows a core with a thickness of 0.020 inches, the core thickness can range from 0.0005 to 0.050 inches.

[0031] With reference to FIGURES 4A-4E, each of the four bends in the metal sheet that make up the core 120 should have a radius of 0.060 inches in the preferred embodiment. More specifically, the arc of each bend should form a quarter circle having a radius of 0.060 inches. These precise bends apply to the bends between all surfaces of the core 120. In addition, it is also important to note that the corners 226 of the core also require a radial measurement. Each corner 226 should have a curvature that creates an arc with a maximum radius of 0.020 inches. Accordingly, all corners or edges that form a sharp edge should be ground down or properly finished as sharp corners on the core will reduce the sensing performance. The tolerances for these radius bends and the core measurements listed above are ± 0.005 inches for linear measurements and ± 5 degrees for the right angle bends.

[0032] Since cold bends in the metal change the magnetic properties of the core, an annealing process should be applied to the core to properly complete its construction. Thus, after the bends are made, the core should be cleaned such that all contaminants such as oil, grease, lacquer, and water, are removed from the core surface. In addition, the core should not be exposed to carbon, sulfur, or nitrogen during the annealing process. Once properly cleaned, the core is preferably annealed in an oxygen free, dry hydrogen atmosphere with a dew point below -40 degrees Celsius during the entire hydrogen annealing stage. If multiple cores are annealed at this part of the process, an insulating powder should be used to keep the cores from touching other cores or other objects. Preferred insulating powders include: magnesium, aluminum oxide, clean ceramic paper or an equivalent clean ceramic material.

[0033] The core should be annealed for seven to eight hours at temperature range between 1121 to 1177 degrees Celsius. After the seven to eight hour period, the core should be furnace cooled to a temperature approximate to 593 degrees Celsius. Once the core is cooled to 593 degrees Celsius, the core should be cooled at a rate between 260 and 316 degrees Celsius per hour to 371 degrees Celsius and then furnace cooled until a

room temperature is reached.

[0034] Returning to FIGURE 3, after the core 120 is placed into the housing 102, a spyder 122 is inserted on top of the core 120 to affix the core 120 and the two coil assemblies 118. The spyder 122 is preferably made from a nonconductive material such as a glass filled polymer. An adhesive can be used to secure the spyder 122 to the coils 118. A spring 124 and washer 126 are then placed on the spyder 122 and a snap ring 128 is used to secure the spring 124 and washer 126 to the spyder 122. Machined groves lined in the inside wall of the housing 102 receive the snap ring 128 to hold the snap ring 128 down onto the washer 126 and spring 124.

[0035] The cover 130 can be affixed to the housing 102 by a metal welding with a minimum weld penetration of 0.010 inches. Similar to the housing 102, the cover 130 is preferably made from a non-magnetic material with low conductivity such as titanium or stainless steel.

[0036] A proper seal between the metal cover 130 and the metal housing 102 prevent adverse effects caused by lightning strikes or other external sources of electrical current. This allows the proximity sensor 100 to provide consistent, repeatable proximity detection information even in the presence of relatively strong electromagnetic fields generated by current from a source external to the sensor assembly. For instance, when proximity sensor 100 is installed in an aircraft, the latter may be subjected to lightning strikes having a peak current of 200 KA or more. This current, which sheets along the outer skin of the aircraft, generates electromagnetic fields having an intensity of 10,000 amps/M or more, which fields may intercept the proximity sensor 100 when positioned adjacent to the outer skin of the aircraft. Such fields could temporarily adversely affect the operation of proximity sensor 100 by saturating core, thereby causing the inductance of coil to decrease to a level indicative of a magnetic target.

[0037] The embodiment of proximity sensor 100 in accordance with the present invention shown in FIGURE 5 is constructed in a manner similar to the proximity sensor shown in FIGURES 2 and 3. The main difference in the embodiment of FIGURE 5 is that a calibration bolt 132 is inserted through the center of the core 120'. The calibration bolt 132 is used to change the level of inductance that is measured from the coils to accommodate the external circuitry.

[0038] Much like the material of the core 120', the calibration bolt 132 is preferably constructed from a highly permeable material such as soft iron, cast iron, transformer steel, or any other like material. The calibration bolt 132 should have a relative permeability of approximately 90 or higher. As with the material of the core 120', the performance of the device is increased as the relative permeability of the calibration bolt 132 is increased.

[0039] As shown in FIGURE 5, the calibration bolt 132 should be positioned to extend through the center of the core 120' and into a hole 121 in the center of the spyder 122. The calibration bolt 132 should be positioned such

that it is substantially perpendicular to the head surface of the core 120'. The calibration bolt 132 can be formed into a threaded screw to facilitate the calibration process.

[0040] The core utilized in the embodiment employing the calibration bolt 132, shown in FIGURES 6A-6D, is similar to the core of FIGURE 4A-4D. The core 120' of FIGURES 6A-6D comprises a substantially flat, rectangular member bent in four locations to form a shape that resembles a rectangular Greek omega character having a head portion 220', two legs 222', and two foot portions (feet) 224'. The core of FIGURES 6A-6D also comprises an aperture in the center of the head portion 220' sized to receive the calibration bolt 132. In addition, the center of the head portion 220' has an extended width to provide additional strength to the core's structure and to improve the sensitivity of the proximity sensor.

[0041] The core 120' of FIGURES 6A-6D is also shaped with bends at right angles so that the head portion 220' is perpendicular to the two legs 222', and the two legs are perpendicular to the two feet 224'. The two feet 224' are parallel to each other and coplanar, extend oppositely from the respective legs. Both feet portions 224' are also parallel to the head portion 220'.

[0042] The top section of each of the two legs has a width equal to the width of the head portion 220', and the bottom section of each leg 222' has a width that is more narrow than the width of the top section. The wider top section should extend down each leg approximately 0.050 inches. Accordingly, the more narrow bottom section of the each leg should extend down the remaining portion of each leg having a length of approximately 0.250 inches.

[0043] Similar to the core 120 of FIGURES 3A-3D, each of the four bends in the metal sheet that make up the core 120' should have a precise radius bend of 0.060 inches. More specifically, the arc of each bend should form a quarter circle having a radius of 0.060 inches. These precise bends apply to the bends between all surfaces of the core 120'. In addition, it is also important to note that the corners 226' of the core also require a radial measurement. Each corner 226' should have a curvature that creates an arc with a maximum radius bend of 0.020 inches. Accordingly, all corners or edges that form a sharp edge should be ground down or properly finished, as sharp corners on the core will reduce the sensing performance. The tolerances for these radius bends and the core measurements listed above are ± 0.005 inches for linear measurements and ± 5 degrees for the right angle bends.

[0044] As described above, the proximity sensor 100 is used to detect three different types of objects. In one mode of operation, the proximity sensor 100 is used to detect the presence of objects that emit a magnetic field such as a magnetically charged iron. When used in this mode of operation, the proximity sensor 100 operates as a saturated core sensor. In another mode of operation, the proximity sensor 100 is used to detect the pres-

ence of permeable objects, also known as ferromagnetic metals. When used in this second mode of operation, the proximity sensor 100 operates as a variable reluctance sensor. In yet another mode of operation, the proximity sensor 100 is used to detect the presence of conductive metals or nonferrous objects such as aluminum, copper, brass or other like metals. When used in this third mode of operation, the proximity sensor 100 operates as an eddy current loss sensor.

[0045] FIGURE 7 illustrates the proximity sensor 100 used as a saturated core sensor to detect a magnetic object 301. The target facing surface 104 of the proximity sensor 100 is directed toward a magnetic object 301 producing a magnetic field 302. As the magnetic object 301 moves toward the proximity sensor 100, a point is reached where flux lines 302 begin to enter the core 120 and follow the core as the least reluctant path. As the proximity sensor 100 is moved deeper into the magnetic field, the core 120 begins to react to the magnetic field, thus changing the impedance value of the coils surrounding the core 120. Eventually, the core reaches a level of saturation where the impedance value of the coil significantly reacts to the changed state of the core 120. This reaction in the impedance value in relation to the saturation level is shown in FIGURE 8.

[0046] FIGURE 8 is a graph of the coil impedance versus the distance between the magnetic object and the proximity sensor 100. As illustrated by the line 310, when the magnetic object 301 reaches a distance of approximately 0.8 inches (indicated by point A), the core begins to saturate. From this distance of 0.8 inches, as the magnetic object 301 moves toward the proximity sensor 100, the impedance significantly decreases as the core begins to saturate. When the core saturates, the impedance of coil drops rapidly from a relatively high value representing virtually no saturation of the core to a relatively low value representing virtually complete saturation of the core. The "no saturation" inductance level is represented by the upper horizontal portion of inductance curve 310 in FIGURE 8, and the "complete saturation" inductance level is represented by the lower horizontal portions of curve 310.

[0047] Thus, by measuring the impedance levels in the coils, the presence of a magnetic object can be detected. The physical dimensions of the core determine when the core reaches magnetic saturation. The unique design of the present invention provides optimal performance of a saturated core proximity sensor as characterized in the graph of FIGURE 8. As a result of the unique shape and dimensions of the core, the core will saturate at a greater distance away from the magnetic field source than a conventional U-type core of an equivalent size.

[0048] When the proximity sensor 100 is used as a variable reluctance sensor, the configuration of the proximity sensor 100 is somewhat different than the configuration shown in FIGURE 7. FIGURE 9 shows an apparatus 303 with the proximity sensor 100 adjacent to a

permeable target 306. When the proximity sensor 100 is used as a variable reluctance sensor, the proximity sensor 100 generates an alternating magnetic field as illustrated by the flux lines 304.

[0049] To detect the presence of permeable materials, an external alternating current source is used to drive the coils of the proximity sensor 100. When the permeable target 306 is moved into the magnetic field of the proximity sensor 100, the reluctance between the permeable target 306 and proximity sensor 100 changes. This change in reluctance increases the inductance of the sensing coils. Thus, an inductance measuring circuit can be used to detect the presence of the permeable target 306.

[0050] FIGURE 10 is a graph of the coil sensitivity as a function of the distance between a permeable target 306 and the proximity sensor 100. The sensitivity of the proximity sensor 100 is measured in units of microhenrys per Mil. For example, if the conductive target 306 moves one Mil, with a distance of 0.14 inches between the proximity sensor and the conductive target, the coils' inductance changes by five microhenrys (as indicated by point B). If the permeable target 306 is 0.02 inches away from the proximity sensor 100 and moves one Mil, the coils' inductance changes by 42 microhenrys (as indicated by point C). The sensitivity of the proximity sensor 100 increases at an exponential rate as the permeable target 306 moves toward the proximity sensor 100. In this configuration, the coil inductance increases as the permeable target 306 moves toward the proximity sensor 100.

[0051] When the proximity sensor 100 is used as an eddy current loss sensor to detect conductive targets, the configuration of the proximity sensor 100 is similar to the configuration of the variable reluctance sensor as shown in FIGURE 9. However, the inductance of the coils has a different reaction to the conductive targets compared to the permeable targets.

[0052] The proximity sensor shown in FIGURE 9 is also used to describe the eddy current configuration, only the target 306 now consists of a conductive, non-permeable target such as aluminum or copper. When the conductive target 306 is moved into the magnetic field 304 of the proximity sensor 100, the conductive target 306 will intercept a portion of the magnetic field 304 produced by the alternating current fed into the coil. This interception of the magnetic field 304 induces eddy currents in the conductive target 306 that are temporally (ninety degrees) out of phase with the source current. In turn, these eddy currents do two things; they dissipate energy as heat within the conductor and generate another magnetic field. The magnetic field generated by the eddy currents within the conductive target 306 opposes the magnetic source field 304 eventually causing additional currents back in the sensor coils. Thus, when the conductive target 306 enters the magnetic source field 304, the current in the coils increases. This reaction in the current level is detected by electronic circuitry that

measures the inductance over the coil. When the conductive target 306 moves toward the proximity sensor 100, the inductance of the coils decreases, thereby indicating the presence of the conductive target 306. FIGURE 11 is a graph of the coil sensitivity as a function of the distance between a conductive target and the proximity sensor. Similar to the graph of FIGURE 10, the sensitivity of the proximity sensor 100 is measured in units of microhenrys per Mil. For example, if the conductive target moves one Mil, with a distance of 0.03 inches between the proximity sensor and the conductive target, the coils' inductance changes by eight microhenrys (as indicated by point D). In this configuration, the inductance of the coils decreases as the conductive target is moved toward the proximity sensor. Thus, the present invention provides a highly sensitive proximity sensor that operates in the eddy current loss mode to detect the presence of a conductive, non-permeable target by simply measuring the inductance in the coils.

[0053] The graph of FIGURE 11 also displays the performance levels of the proximity sensor 100 at different operating frequencies. The first line 312 reveals the sensitivity of the proximity sensor when the source current is at 2 KHz. As shown by the other lines 314-320 corresponding with other operating frequencies of 5, 6, 7 and 8 KHz, the performance of the proximity sensor peaks at 8 KHz and decreases as the frequency increases.

[0054] As with the embodiment utilizing the proximity sensor as a saturated core sensor, the physical dimensions of the core, together with the dimensions and configuration of the coil, determine the sensor's ability to detect targets at an optimal distance. The unique design of the core and the placement of the coils provide a variable reluctance and eddy current loss proximity sensor having the performance characterized in the graphs of FIGURES 10 and 11. As a result of the unique shape and dimensions of the core, the proximity sensor 100 is able to detect variations in the source magnetic field (304 of FIGURE 9) at a greater distance away from the proximity sensor 100 than a conventional U-type core of an equivalent size.

[0055] FIGURES 12, 13A and 13B show another embodiment of a proximity sensor 1200 having a cup core 1220 in accordance with the present invention. This embodiment includes a housing 1201 having a target-facing front surface 1251 and a cylindrical sidewall 1252 extending from the front surface 1251. The sidewall 1252 and the front surface 1251 form a hollow interior region in the housing 1201. As shown diagrammatically in broken lines in FIGURE 12, a sensing region 1250 extends out from the target-facing front surface 1251 in a generally hemispherical shape. For example, in an exemplary embodiment, the proximity sensor 1200 can have an effective sensing region of approximately 0.3 inches in a direction perpendicular to the surface 1251. Similar to the operation of the cores shown in FIGURES 4A-4E and 6A-6D, the proximity sensor 1200 of FIGURE 12 is effective for detecting magnetic, permeable, and

non-permeable conductive metallic targets in the sensing region 1250.

[0056] The housing 1201 is preferably made of a durable, nonmagnetic material having a fairly low electrical conductivity, i.e., a conductivity level approximate to the conductivity level of titanium. It is preferred that a physically strong, low conductivity, noncorrosive and nonmagnetic material, like titanium or stainless steel, be used in the construction of the housing 1201. However, to maximize the performance of the proximity sensor, other nonconductive materials such as formable plastics can be used to construct the housing 1201. The performance of the sensor increases as the conductivity of the housing 1201 decreases. The use of highly conductive materials should be avoided because eddy currents may form on the housing surface and reduce the effective range 1250 of the proximity sensor 1200. In addition, the use of ferromagnetic materials should be avoided because the housing 1201 may contain the sensing field produced by the proximity sensor 1200.

[0057] The housing 1201 includes an opening to the hollow interior that is preferably positioned opposite the front surface 1251. The opening in the housing 1201 allows for the insertion of the internal components of the proximity sensor 1200. As known to one of ordinary skill in the art, a hollowed cylinder housing, such as the housing 1201, can be formed from a machining process. Referring now to FIGURES 13A and 13B, in one embodiment the proximity sensor 1200 is assembled by sliding an insulator 1202 into the opening of the housing 1201. The insulator 1202 is preferably constructed from a nonconductive material such as plastic or Mylar with a thickness approximate to 3 Mils. The insulator 1202 may be molded into a cup-shaped form to provide an insulating shield between a coil assembly 1203 and the housing 1201.

[0058] As shown in FIGURE 13A, the coil assembly 1203 is affixed to a flex circuit 1204 and, in one embodiment, the flex circuit 1204 is affixed to the coil assembly 1203 by a solder joint or another like bonding material. The coil assembly 1203 is constructed of a disc shaped bracket and sized to be inserted into the insulator 1202. More specifically, the coil assembly 1203 is formed into a disk having an aperture through the center of the disk. The coil assembly 1203 also comprises a bobbin having a hollowed interior formed to receive a wire coil. The wire coil housed inside the coil assembly 1203 is configured to allow a plurality of wire windings to surround the aperture of the coil assembly 1203. The flex circuit 1204 is preferably constructed from a thin flexible polyimide tape with embedded copper traces (not shown). The copper traces extend from the coil assembly 1203 to a pair of conductors 1211 and provide electronic communication between the coil assembly 1203 and conductors 1211.

[0059] Also shown in FIGURES 13A and 13B, a cup core 1220 having an aperture therethrough is positioned such that the flex circuit 1204 passes through the aper-

ture of the coil core 1220. Details of the construction of the cup core 1220 are described in further detail below with reference to FIGURES 14A and 14B. Generally described, the cup core 1220 is sized to be received in the opening of the housing 1201. In addition, the cup core 1220 comprises an annular groove sized to receive the coil assembly 1203. As shown in FIGURES 13A and 13B, once the coil assembly 1203 is inserted into the annular groove of the cup core 1220, the wire coils housed in the coil assembly 1203 are then positioned to wind around the annular groove of the cup core 1220. In addition, the conductive ends of the wire coil housed in the coil assembly 1203 are positioned to pass through the aperture of the cup core 1220 and follow the flex circuit 1204 such that they are led to and electronically conducted to the pair of conductors 1211. In one embodiment, the wire in the coil assembly 1203 comprises approximately 474 turns of 42-gauge wire. Once the coil assembly 1203, flex circuit 1204, and cup core 1220 are combined, the components are then slidably inserted into the insulator 1202 positioned in the housing 1201.

[0060] Details of the cup core 1220 are best seen in FIGURES 14A and 14B. In one embodiment, the cup core 1220 comprises a generally cylindrical shaped cup having an annular groove in an upper surface 1221 of the cup core 1220. The upper surface 1221 of the cup core 1220 is substantially planar and when installed into the housing 1201, the upper surface 1221 is substantially parallel to the sensing surface 1251 of the housing 1201. The cup core 1220 further comprises a bottom surface 1223 having a circular cavity extending from the bottom surface 1223 toward the upper surface 1221. The circular cavity is positioned in the center of the cup core 1220 and configured to extend at a right angle from the bottom surface 1223. The cup core 1220 further comprises an aperture 1222 extending inwardly from a bottom surface 1223 of the cup core 1220 to facilitate the passage of the flex circuit 1204 and/or wire (not shown).

[0061] As seen in FIGURE 14B, a diametric section of the cup core 1220 comprises a head portion 1231, two legs 1232, and two foot portions (feet) 1233. The head portion 1231 forms a substantially planar section along the upper surface 1221 and is perpendicular to the sectional direction created by the two legs 1232. The sectional direction of the two legs 1232 is perpendicular to the sectional direction of the two feet 1233. The two feet 1233 are in a common plane along the bottom surface 1223. Both feet 1233 are parallel to the head portion 1231. In addition, the section of the cup core 1220 comprises two tail portions (tails) 1234. Each tail 1234 extends from the outer edges of the two feet 1233. The sectional direction of the tails 1234 are perpendicular to the sectional direction of the two feet 1233.

[0062] In one exemplary embodiment, as shown in the section of FIGURE 14B, the head portion 1231 of the cup core 1220 has a width of 0.200 inches, which is equal to the outer diameter of the center post 1235

shown in FIGURE 14A. The two legs 1232 extending at right angles from the head portion 1231 have a preferred height of 0.144 inches measuring from the top surface to the bottom surface. The two legs 1232 create one side of the annular ring, and the annular ring has a depth of 0.124 inches. The two feet 1233 extend away from each other from the two legs. Each foot portion 1233 has a preferred length of 0.16675 inches that measures from the outer perimeter of the core to the inside of the two legs 1232. In this embodiment, each tail 1234 has a preferred length of 0.144 inches, and each tail 1234 is generally parallel to the legs 1232. The surfaces of the head 1231, leg 1232, feet 1233 and tail 1234 portions have a thickness of 0.02 inches.

[0063] The annular groove is created by the surfaces of the leg 1232, feet 1233 and tail 1234 portions. In one embodiment, the depth of the annular groove is 0.124 inches. Each of the four corner edges or fillets 1240 in the bottom of the annular groove should have a radius of 0.015 inches, where each bend or fillet 1240 should form a quarter circle having that radius. The tail portions 1234 have a preferred height of 0.144 inches.

[0064] In another embodiment, the two legs of the cup core extend at right angles from the head portion and have a preferred height of 0.174 inches measuring from the top surface to the bottom surface. The two legs create one side of the annular ring and, in this embodiment, the annular ring has a depth of 0.154 inches. Each tail has a preferred length of 0.174 inches, and each tail is generally parallel to the legs. In this embodiment, the surfaces of the head, leg, feet and tail portions have a thickness of 0.02 inches.

[0065] The cup core 1220 is preferably constructed from a high permeable material such as soft iron, cast iron, transformer steel, or any of the like material. The relative permeability should be at least 10,000. Although a relative permeability is suggested to be at least 10,000, higher values are desired to increase the sensor's performance. One material that is preferred is referred to in the art as HyMu "80"®, available from Carpenter Steel Company of New Jersey.

[0066] In one embodiment, the cup core 1220 is formed by a machining process of one solid piece of metal. Since the machining process creates changes in the magnetic properties of the core metal, an annealing process should be applied to the core to properly complete its construction. Thus, after the machining process is complete to form the cup core 1220 into the above-described specifications, the cup core 1220 should be cleaned so that all contaminants such as oil, grease, lacquer and water are removed from the core surface. In addition, the core should not be exposed to carbon, sulfur, or nitrogen during the annealing process. Once properly cleaned, the core is preferably annealed in an oxygen free, dry hydrogen atmosphere with a dew point below -40°C during the entire hydrogen annealing stage. If multiple cores are annealed at this part of the process, an insulating powder should be used to keep

the cores from touching one another or other objects. Preferred insulating powders include: magnesium, aluminum oxide, clean ceramic paper, or an equivalent cleaning ceramic material.

[0067] The core should be annealed for 7-8 hours at a temperature of 1,121°-1,177°C. After the 7-8 hour period, the core should be furnace cooled to a temperature of approximately 593°C. Once the core is cooled to 593°C, the core should be cooled at a rate between 260° and 316°C per hour to 371°C, and then furnace cooled until room temperature is reached.

[0068] Returning again to FIGURES 13A and 13B, the construction of the proximity sensor 1200 is continued where a spring 1206, washer 1207, and a carrier assembly 1208 are respectively inserted into the housing 1201 to hold the cup core 1220, coil assembly 1203 and flex circuit 1204 in place. In this step, the spring may be fixed to the cylindrical bracket 1205 by the application of an RTV adhesive. The carrier assembly 1208 comprises a hollow cylindrical housing having two sections, wherein a leading section has a diameter sized to be inserted into the bore of the spring 1206 and the cylindrical bracket 1205. The trailing section of the carrier assembly 1208 has a larger diameter sized to be slidably inserted into the housing 1201 and yet large enough to produce a shoulder to engage upon the adjacent end of the spring 1206. Once the spring 1206, washer 1207, and carrier assembly 1208 are inserted into the housing 1201, a connector assembly 1209 is used to seal the opening of the housing 1201 and hold the assembly together with the spring 1206 partially compressed.

[0069] As shown in FIGURE 13A and 13B, the connector assembly 1209 comprises a generally cylindrical body sized to be inserted into the opening of the housing 1201 and to create an air tight seal around the opening of the housing 1201. The connector assembly 1209 has at least two internal electronic connectors 1211 and at least two external electric conductors 1210 for producing an electronic communication channel between the outer portion of the housing 1201 and the conductors internal to the housing 1201. The connector assembly 1209 may create a seal with the opening of the housing 1201 by the use of threaded or mechanical locking devices. Although threaded and mechanical locking devices are used in this embodiment, any mechanical device or adhesive may be used to create a seal between the connector assembly 1209 and the housing 1201.

[0070] As described above, the various embodiments of the proximity sensor are used to detect three different types of objects. In one mode of operation, the proximity sensor is used to detect the presence of objects that emit a magnetic field, such as magnetically charged iron. When used in this mode of operation, the proximity sensor operates as a saturated core sensor. In another mode of operation, the proximity sensor is used to detect the presence of permeable objects, known as ferromagnetic metals. When used in this second mode of operation, the proximity sensor operates as a variable reluc-

tance sensor. In yet another mode of operation, the proximity sensor is used to detect the presence of conductive metals or non-ferrous objects, such as aluminum, copper, brass, or other like materials. When used in this third mode of operation, the proximity sensor operates as an eddy current loss sensor.

[0071] Referring again to FIGURE 13A, various circuit configurations (box 1225) that create a closed circuit loop in the wire of the proximity sensor 1200 can be used to produce each mode of operation described above. Each circuit described above with reference to FIGURE 3, can be used to produce the various operating modes of the proximity sensor. For instance, any circuit configured to measure impedance can be used with the proximity sensor. In this embodiment, a circuit can be used to measure the impedance over the conductor housed in the core to ultimately detect the presence of an object.

[0072] In yet another embodiment, an Eddy Current Kill Oscillator (ECKO) circuit can be configured in box 1225 of FIGURE 13A to allow the proximity sensor 1200 to operate as an eddy current loss sensor. As known to one having ordinary skill in the art, an ECKO circuit is generally described as an oscillator circuit that oscillates at a frequency defined by a tank circuit. One example of an ECKO circuit is commercially available from the MICRO SWITCH division of the Honeywell Corporation.

[0073] The tank circuit is composed of a sensor (inductance and resistance) in parallel with a capacitor. To calibrate the ECKO circuit to a certain actuation point, a calibration resistor is adjusted to match the resident impedance of the tank circuit, e.g., Z at 0° phase. As long as the resident impedance of the tank is above the impedance of the calibration resistor, the circuit will oscillate. As will be described in more detail below with reference to FIGURE 16, when a target moves toward the proximity sensor closer than the actuation point, the real losses increase and the oscillator eventually ceases operation.

[0074] In yet another embodiment, the ECKO circuit and proximity sensor 1200 can be configured with specific components to operate in a saturated core mode (SCORE), this embodiment can be referred to an Eddy Current Loss All Metal Sensor (ECAMS)TM. In this embodiment, the capacitor in the ECKO circuit comprises a 1,800 picofarad capacitor in the tank circuit. This configuration causes the tank to oscillate at 28 kHz and reduces the amount of variance over temperature providing the best sensitivity to the proximity sensor. In this embodiment, the coil can comprise of 900 turns of 42-gauge wire. As described above, the target utilized with the SCORE sensor is a magnet target.

[0075] Another embodiment of a proximity sensor 1500 having a cup core 1220 is shown in FIGURE 15A and 15B. The embodiment of FIGURE 15A and 15B generally comprises the components of the embodiment depicted in FIGURES 13A and 13B. More specifically, the embodiment of FIGURE 15A and 15B comprises a housing 1501 with a sensing surface 1550 and

cylindrical wall 1540 that is substantially perpendicular to the sensing surface 1550. The housing 1501 comprises a hollow center inside of the cylindrical wall 1540 and an opening to allow the insertion of the various components described below. As shown in FIGURE 15B, an insulator cup 1502 is slidably inserted into the opening of the housing 1501. The construction of the insulator cup 1502 is constructed similar to that of the embodiment depicted in FIGURES 13A and 13B, except the insulator cup 1502 is sized to produce an electronically insulating shield between the housing 1501 and a coil assembly 1503. The proximity sensor 1500 also comprises a spring cushion 1504, which secures the carrier assembly 1508 into position.

[0076] Similar to the embodiment of FIGURES 13A and 13B, the coil assembly 1503 comprises a plastic bobbin which houses a plurality of wire windings wherein the coil assembly 1503 and the wire windings are sized to be inserted into the hollow portion of the cup core 1220. The spring cushion 1504 is constructed of a silicon rubber and shaped in a disk configuration and sized to be slidably inserted into the hollow portion of the cup core 1220. The spring cushion 1504 functions as a brace for the coil assembly 1503 such that coil assembly 1503 can be affixed into a locked position inside the hollow portion of the cup core 1220. The coil assembly 1503, spring cushion 1504 and the cup core 1220 are slidably inserted into the insulator cup 1502 positioned in the housing 1501. The spring 1506 has been placed on top of the cup core 1220 and, may be affixed to the cup core 1220 by the use of a RTV adhesive.

[0077] Similar to the embodiment of FIGURES 13A and 13B, the coil assembly 1503, spring cushion 1504 and cup core 1220 are configured to accommodate a wire winding 1509 that creates a wire coil inside the coil assembly 1503 having approximately 900 rotations, wherein the conductive ends of the wires are routed through the spring cushion 1504, the cup core 1220, and eventually routed into a carrier 1508 and ultimately connected to a substrate assembly 1510. The carrier assembly 1508 is of similar construction to the carrier assembly of FIGURES 13A and 13B, however, the carrier assembly 1508 comprises a hollowed inner portion sized to receive a substrate assembly 1510.

[0078] The substrate assembly 1510 may comprise a circuit board for carrying any type of circuitry that may be used with the proximity sensor 1500. The above-described electronic circuitry can be constructed on the substrate assembly 1510, and the circuitry electronically is connected to the wire 1509 and the external conductors 1515 via a set of conductors 1511. The substrate assembly 1510 is inserted into the carrier assembly 1508 and secured into place by an adhesive. The connector assembly 1512 is then secured to the opening of the housing 1501, thereby creating a seal between the connector assembly 1512 and the housing 1501.

[0079] As will be explained below, detection of a target object will cause a change in the state of the circuit cou-

pled to the coil which, in turn, can be used to energize a device, turn on a switch, transmit a signal, etc. For example, FIGURE 16 shows one embodiment of a proximity sensor 1200 having a housing 1201 and illustrates a radial section of the cup core 1220, which is used as a saturated core (SCORE) sensor to detect a magnetic object 1251. The target facing surface 1251 of the proximity sensor is directed toward a magnetic object 901 producing a magnetic field 902. As the magnetic object 901 moves toward the proximity sensor 1200, a point is reached where flux lines 902 begin to enter the core 1220 and follow the core as the path of least reluctance. As the proximity sensor 1200 is moved deeper into the magnetic field, the core 1220 begins to react to the magnetic field, thus changing the impedance value of the wire coils 1275 that are placed in the annular groove of the cup core 1220. Eventually, the cup core 1220 reaches a level of saturation where the impedance value of the coil significantly reacts to the changed state of the cup core 1220. This reaction in the inductance value in relation to the saturation level is shown in FIGURE 17.

[0080] FIGURE 17 is a graph of the coil inductance versus the distance between the magnetic object 901 and the proximity sensor 1200. As illustrated by the line 910, when the magnetic object 901 reaches a distance of approximately 0.3 inches (indicated by point A), the core begins to saturate. From this distance of 0.3 inches, as the magnetic object 901 moves toward the proximity sensor 1200, the impedance significantly decreases as the cup core begins to saturate. When the cup core saturates, the impedance of coil drops rapidly from a relatively high value representing virtually no saturation of the core to a relatively low value representing virtually complete saturation of the cup core. The "no saturation" inductance level is represented by the upper horizontal portion of inductance curve 910 in FIGURE 17, and the "complete saturation" inductance level is represented by the lower horizontal portion of curve 910.

[0081] Thus, by measuring the impedance levels in the coils, the presence of a magnetic object can be detected. The physical dimensions of the core determine when the core reaches magnetic saturation. The unique design of the present invention provides optimal performance of a saturated core proximity sensor as characterized in the graph of FIGURE 17. As a result of the unique shape and dimensions of the cup core, the cup core will saturate at a greater distance away from the magnetic field source than a conventional prior art core of an equal size.

[0082] When the proximity sensor 1200 is used as a variable reluctant sensor, the configuration of the proximity sensor 1200 is somewhat different than the configuration shown in FIGURE 16. In one example, a proximity sensor may be configured as a variable reluctance sensor to sense a permeable target. FIGURE 18 shows an apparatus 1800 with a proximity sensor 1200 adjacent to a permeable target 908. When the proximity sensor 1200 is used as a variable reluctance sensor, the

proximity sensor 1200 generates an alternating magnetic field as illustrated by the flux lines 903.

[0083] To detect the presence of permeable materials, an external alternating current source is used to drive the coils 1276 of the proximity sensor 1200. When the permeable target 908 is moved into the magnetic field of the proximity sensor 1200, the reluctance between the permeable target 908 and the proximity sensor 1200 changes. This change in reluctance increases the inductance of the sensing coils 1276. Thus, an inductance measuring circuit can be used, such as one of the circuits described above, to detect the presence of the permeable target 908.

[0084] FIGURE 19 is a graph of the coil sensitivity as a function of the distance between the permeable target 908 and the proximity sensor 1200. The sensitivity of the proximity sensor 1200 is measured in units of microhenrys per Mil. For example, if the conductive target 908 moves one Mil, the distance of 0.060 inches between the proximity sensor 1200 and the target 908, the coils' inductance changes by approximately 19 microhenrys (as indicated by point B). If the permeable target 908 is 0.04 inches away from the proximity sensor 1200 and moves one Mil, the coils' inductance changes by approximately 28.6 microhenrys (as indicated by point C). The sensitivity of the proximity sensor 1200 increases at an exponential rate as the permeable target 908 moves toward the proximity sensor 1200. In this configuration, the coil inductance increases as the permeable target 908 moves toward the proximity sensor 1200.

[0085] When the proximity sensor is used as an eddy current loss sensor to detect conductive targets, the configuration of the proximity sensor 1200 is similar to the configuration of the variable reluctance sensor as shown and described above. However, the inductance of the coils has a different reaction to the conductive targets compared to the permeable targets.

[0086] The proximity sensor 1200 shown in FIGURE 18 is also used to describe the eddy current configuration, only the target 908 now consists of a conductive, non-permeable target such as aluminum or copper. When the conductive target 908 is moved into the magnetic field 903 of the proximity sensor 1200, the conductive target 908 will intercept a portion of the magnetic field 903 produced by the alternating current fed into the coil 1276. This interception of the magnetic field 903 induces eddy currents in the conductive target 908 that are temporally (90 degrees) out-of-phase with the current source. In turn, these eddy currents do two things: they dissipate energy as heat within the conductor; and they generate another magnetic field. The magnetic field generated by the eddy currents within the conductive target 908 opposes the magnetic source field 903 eventually causing additional currents back in the sensor coils. Thus, when the conductive target 908 enters the magnetic source field 903, the current in the coils increases. This reaction in the current level is detected by electronic circuitry that measures the inductance

over the coil. When the conductive target 908 moves toward the proximity sensor 1200, the inductance of the coils decreases, thereby indicating the presence of the conductive target 908.

[0087] As with the embodiment utilizing the proximity sensor as a saturated core sensor, the physical dimensions of the core, together with the dimensions and the configuration of the coil, determine the sensor's ability to detect targets at an optimal distance. The unique design of each core disclosed and described above, and the placement of the coils provide a variable reluctance and eddy current loss proximity sensor having the performance characterized in the graphs described above. As the result of the unique shape and dimensions of the above-described cores, a proximity sensor is able to detect variations in the source magnetic field at a greater distance away from the proximity sensor than a conventional core having an equivalent size.

[0088] While the preferred embodiment of the invention has been illustrated and described, it will be appreciated that various changes can be made to it without departing from the scope of the claims.

Claims

1. A proximity sensor, comprising:
 - a core having a section including a central part, two foot portions on opposite sides of the central part and two legs each extending between one of the foot portions and the central part, wherein the two legs are positioned on opposite sides of the central part;
 - a first sensing coil positioned around core; and
 - a circuit coupled to the first sensing coil for sensing an object located in a sensing region adjacent to the core, wherein the core and circuit are configured and arranged to detect the presence of ferromagnetic, non-permeable and magnet targets.
2. The proximity sensor of Claim 1, wherein the legs are elongated and extend transversely of the central part and the foot portions.
3. The proximity sensor of Claim 1, further comprising a second sensing coil positioned around the core, wherein the first and second sensing coils have turns wrapped around the legs.
4. The proximity sensor of Claim 3, wherein the circuit also energizes the sensing coil to create the sensing region of the core.
5. The proximity sensor of Claim 1, wherein the circuit includes an oscillator for energizing the sensing coil to create the sensing region.
6. The proximity sensor of Claim 5, wherein the oscillator includes an eddy current kill oscillator circuit.
7. The proximity sensor of Claim 5, wherein the oscillator includes an eddy current loss all metal sensor circuit.
8. The proximity sensor of Claim 1, wherein the core is made of a permeable material.
9. The proximity sensor of Claim 1, wherein the core is constructed from a substantially rectangular member having a plurality of substantially rectangular surfaces forming the central part, foot portions and legs, each defining a plane, the plane of the central part being substantially perpendicular to the plane of each of the legs, the plane of the central part being substantially parallel to the plane of each of the foot portions, the first and second foot portions being adjacent to the first and second legs, respectively.
10. The proximity sensor of Claim 8, wherein the width of the central part of the core is greater than the width of the two leg portions and the foot portions.
11. The proximity sensor of Claim 1, wherein the core has a thickness of approximately 0.020 inches.
12. The proximity sensor of Claim 1, wherein the central part of the core has a width of approximately 0.370 inches and a length of approximately 0.390 inches.
13. The proximity sensor of Claim 1, wherein the legs have a first width adjacent to the central part and a second width, different from the first width, remote from the central part.
14. The proximity sensor of Claim 1, wherein the leg portions have a length of approximately 0.300 inches, a first width of approximately 0.370 inches extending approximately 0.050 inches from the central part, and a second width of approximately 0.292 inches extending approximately 0.250 inches beyond the first width.
15. The proximity sensor of Claim 1, further comprising a housing supporting the sensing coil and the core.
16. The proximity sensor of Claim 1, in which the central portion of the core includes a calibration bolt
17. The proximity sensor of Claim 16, wherein the calibration bolt is made of a highly permeable material.
18. The proximity sensor of Claim 16, wherein the calibration bolt is made of a material selected from the group consisting of soft iron, cast iron, and trans-

former steel.

19. The proximity sensor of Claim 16, wherein the calibration bolt is made of a material having a relative permeability equal to or greater than 90.
20. The proximity sensor of Claim 16, wherein the position of the calibration bolt relative to the remainder of the central part is adjustable to change a level of inductance that is measured from the first sensing coil positioned around core.
21. The proximity sensor of Claim 16, wherein the calibration bolt is a threaded screw.
22. The proximity sensor of Claim 1, wherein the cross-sectional shape of the core further comprises two tail portions, wherein each tail portion extend from an outer edge of one of the two foot portions, and wherein the tail portions are perpendicular to two foot portions.
23. The proximity sensor of Claim 1, wherein the head portion forms a substantially planar upper surface of the core and is perpendicular to the direction created by each of the two leg portions, the direction of the two leg portions being perpendicular to the direction of the two foot portions, the two foot portions lying in a common bottom surface plane, and wherein the two leg portions form an annular groove in the core that opens along side the upper surface of the core.
24. A core for use in a proximity sensor, wherein the core comprises a section of omega shape having a central part, two foot portions on opposite sides of the central part and two legs portions each extending between one of the foot portions and the central part, wherein the core is made from a highly permeable material.
25. The core of Claim 24, wherein the leg portions are elongated and extend transversely of the central part and the foot portions.
26. The core of Claim 24, wherein the core is constructed from a substantially rectangular member having a plurality of substantially rectangular surfaces forming the central part, foot portions and legs, each defining a plane, the plane of the central part being substantially perpendicular to the plane of each of the legs, the plane of the central part being substantially parallel to the plane of each of the foot portions, the first and second foot portions being adjacent to the first and second legs, respectively.
27. The core of Claim 24, wherein the core has a thickness of approximately 0.020 inches.
28. The core of Claim 24, wherein the central part of the core has a width of approximate by 0.370 inches and a length approximate to 0.390 inches.
29. The core of Claim 24, wherein the legs have a first width adjacent to the central part and a second width, different from the first width, remote from the central part.
30. The core of Claim 24, wherein the leg portions have a length of approximately 0.300 inches, a first width of approximately 0.370 inches extending approximately 0.050 inches from the central part, and a second width of approximately 0.292 inches extending approximately 0.250 inches beyond the first width.
31. The core of Claim 24, wherein the width of the central part is greater than the width of the leg portions and the foot portions.
32. The core of Claim 24, in which the central part of the core includes a calibration bolt positioned there-through.
33. The proximity sensor of Claim 24, wherein the cross-sectional shape of the core further comprises two tail portions, wherein each tail portion extend from an outer edge of one of the two foot portions, and wherein the tail portions are perpendicular to two foot portions.
34. The core of Claim 24, wherein the central part forms a substantially planar upper surface of the core and is perpendicular to the direction created by each of the two leg portions, the direction of the two leg portions being perpendicular to the direction of the two foot portions, the two foot portions lying in a common bottom surface plane, and wherein the two leg portions define a surface that forms an annular groove in the core that opens from the upper surface of the core.
35. The proximity sensor of Claim 1, further comprising:
a calibration bolt positioned through an aperture in the central part of the core, wherein the calibration bolt is operatively associated with the first sensing coil and the core such that the calibration bolt influences an electric signal measured from the first sensing coil.
36. The proximity sensor of Claim 35, wherein the calibration bolt is made of a highly permeable material.
37. The proximity sensor of Claim 35, wherein the calibration bolt is made of a material selected from the group consisting of soft iron, cast iron, and trans-

former steel.

38. The proximity sensor of Claim 35, wherein the calibration bolt is made of a material having a relative permeability equal to or greater than 90.

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39. The proximity sensor of Claim 35, wherein the position of the calibration bolt relative to the central part is adjustable to change a level of inductance that is measured from the first sensing coil positioned around core.

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40. The proximity sensor of Claim 35, wherein the calibration bolt is a threaded screw.

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41. The proximity sensor of Claim 35, further comprising circuitry coupled to the sensing coil, for sensing an object located in a sensing region adjacent to the core.

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42. The proximity sensor of Claim 41, wherein the circuitry also energizes the sensing coil to create the sensing region of the core.

43. The proximity sensor of Claim 35, wherein the core has a thickness of approximately 0.020 inches.

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44. The proximity sensor of Claim 35, wherein the legs have a first width adjacent to the central part and a second width, different from the first width, remote from the central part.

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45. The proximity sensor of Claim 35, wherein the legs have a length of approximately 0.300 inches, a first width of approximately 0.370 inches extending approximately 0.050 inches from the central part, and a second width of approximately 0.292 inches extending approximately 0.250 inches beyond the first width.

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46. A proximity sensor, comprising:

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a member having a top surface, a bottom surface, and a side surface having a width between the top and the bottom surfaces of the member, wherein the top surface is generally planar, and wherein the member defines a cavity that extends into the member from the top surface, wherein a section of the member includes a central part along the top surface of the member, two foot portions on opposite sides of the central part and two legs, wherein each of the two legs extend between the central part and one foot portion, wherein the foot portions and legs respectively form the bottom surface and the inner surface of the cavity, wherein the top and the bottom surfaces have a thickness less than or equal to 0.06 inches, and

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wherein the member is made from a highly permeable material;

a sensing coil positioned in the cavity for allowing magnetic flux communication between the sensing coil and the core; and

a circuit coupled to the sensing coil for sensing an object located in a sensing region adjacent to the member, wherein the member and the circuit are configured and arranged to detect the presence of ferromagnetic, non-permeable and magnetic targets.

47. The proximity sensor of Claim 46, wherein the top and the bottom surfaces of the member have a thickness less than 0.06 inches and greater than or equal to 0.005 inches.

48. The proximity sensor of Claim 46, wherein the member is constructed from a permeable material.

49. The proximity sensor of Claim 46, wherein the member is generally cylindrical in shape.

50. The proximity sensor of Claim 46, wherein the width of the member is in the range of 0.2 to 5 inches.

51. The proximity sensor of Claim 46, wherein the top surface is spaced radially outwardly of the outer perimeter of the member.

52. A method for detecting the presence of an object which comprises:

providing a core having a section of omega shape including a central part, two foot portions on opposite sides of the central part and two legs each extending between one of the foot portions and the central part; providing at least one sensing coil positioned around the core; and measuring the inductance over the sensing coil, and if the inductance varies over a predetermined range, generating a signal to indicate the presence of the object.

53. The method of Claim 52, wherein the leg portions are elongated and extend transversely of the central part and the foot portions.

54. The method of Claim 52, further comprising providing a second sensing coil positioned around the core.

55. The method of Claim 52, wherein the object comprises a magnetic material.

56. The method of Claim 52, wherein the object comprises a ferromagnetic material.

57. The method of Claim 52, wherein the object comprises a conductive material.

Patentansprüche

1. Näherungssensor, umfassend:

einen Kern mit einem Abschnitt, der einen Mittelteil, zwei Fußabschnitte an einander gegenüberliegenden Seiten des Mittelteils und zwei Beine umfasst, die sich jeweils zwischen einem der Fußabschnitte und dem Mittelteil erstrecken, worin die beiden Beine auf einander gegenüberliegenden Seiten des Mittelteils angeordnet sind;

eine erste Abfühlpule, die um den Kern herum angeordnet ist; und

eine Schaltung, die mit der ersten Abfühlpule gekoppelt ist, um ein Objekt abzufühlen, das sich in einem Abfühlbereich in Nachbarschaft des Kerns befindet, worin der Kern und die Schaltung eine solche Konfiguration und Anordnung haben, dass sie das Vorhandensein von ferromagnetischen, nicht-permeablen und magnetischen Zielen detektieren.

2. Näherungssensor nach Anspruch 1, worin die Beine länglich sind und sich in Querrichtung zum Mittelteil und den Fußabschnitten erstrecken.
3. Näherungssensor nach Anspruch 1, der weiters eine zweite Abfühlpule umfasst, die um den Kern herum angeordnet ist, worin die erste und die zweite Abfühlpule Windungen aufweist, die um die Beine herum gewickelt sind.
4. Näherungssensor nach Anspruch 3, worin die Schaltung auch die Abfühlpule mit Energie beaufschlagt, um den Abfühlbereich des Kerns zu erzeugen.
5. Näherungssensor nach Anspruch 1, worin die Schaltung einen Oszillator umfasst, um die Abfühlpule mit Energie zu beaufschlagen, um den Abfühlbereich zu schaffen.
6. Näherungssensor nach Anspruch 5, worin der Oszillator eine Wirbelstromauf-Neutralisiererschaltung umfasst.
7. Näherungssensor nach Anspruch 5, worin der Oszillator eine Wirbelstromverlust-Ganzmetallsensorschaltung umfasst.
8. Näherungssensor nach Anspruch 1, worin der Kern

aus einem permeablen Material besteht.

9. Näherungssensor nach Anspruch 1, worin der Kern aus einem im Wesentlichen rechteckigen Element konstruiert ist, das eine Vielzahl im Wesentlichen rechteckiger Oberflächen aufweist, die den Mittelteil, Fußabschnitte und Beine bilden, die jeweils eine Ebene definieren, wobei die Ebene des Mittelteils im Wesentlichen senkrecht zur Ebene eines jeden der Beine verläuft, wobei die Ebene des Mittelteils im Wesentlichen parallel zur Ebene eines jeden der Fußabschnitte verläuft, wobei der erste und der zweite Fußabschnitt an das erste bzw. das zweite Bein angrenzen.
10. Näherungssensor nach Anspruch 8, worin die Breite des Mittelteils des Kerns größer ist als die Breite der beiden Beinabschnitte und der Fußabschnitte.
11. Näherungssensor nach Anspruch 1, worin der Kern eine Dicke von etwa 0,020 Zoll aufweist.
12. Näherungssensor nach Anspruch 1, worin der Mittelteil des Kerns eine Breite von etwa 0,370 Zoll und eine Länge von etwa 0,390 Zoll aufweist.
13. Näherungssensor nach Anspruch 1, worin die Beine in Nachbarschaft des Mittelteils eine erste Breite und vom Mittelteil entfernt eine zweite Breite aufweisen, die sich von der ersten Breite unterscheiden.
14. Näherungssensor nach Anspruch 1, worin die Beinabschnitte eine Länge von etwa 0,300 Zoll, eine erste Breite von etwa 0,370 Zoll, die sich etwa 0,050 Zoll vom Mittelteil aus erstreckt, und eine zweite Breite von etwa 0,292 Zoll aufweisen, die sich etwa 0,250 Zoll über die erste Breite hinaus erstreckt.
15. Näherungssensor nach Anspruch 1, der weiters ein Gehäuse umfasst, das die Abfühlpule und den Kern hält.
16. Näherungssensor nach Anspruch 1, bei dem der Mittelabschnitt des Kerns einen Kalibrierungsbolzen umfasst.
17. Näherungssensor nach Anspruch 16, worin der Kalibrierungsbolzen aus einem hochpermeablen Material besteht.
18. Näherungssensor nach Anspruch 16, worin der Kalibrierungsbolzen aus einem Material besteht, das aus der aus Weicheisen, Gusseisen und Transformator-Strahl bestehenden Gruppe ausgewählt ist.
19. Näherungssensor nach Anspruch 16, worin der Kalibrierungsbolzen aus einem Material besteht, das

- eine relative Permeabilität größer oder gleich 90 aufweist.
20. Näherungssensor nach Anspruch 16, worin die Position des Kalibrierungsbolzens in Bezug auf den übrigen Mittelteil eingestellt werden kann, so dass ein induktiver Blindwiderstand verändert wird, der von der ersten Abfühlschule gemessen wird, die um den Kern herum angeordnet ist.
21. Näherungssensor nach Anspruch 16, worin der Kalibrierungsbolzen eine Gewindeschraube ist.
22. Näherungssensor nach Anspruch 1, worin die Querschnittsgestalt des Kerns weiters zwei Schwanzabschnitte umfasst, worin sich jeder Schwanzabschnitt von einer Außenkante eines der beiden Fußabschnitte aus erstreckt und worin die Schwanzabschnitte senkrecht zu zwei Fußabschnitten verlaufen.
23. Näherungssensor nach Anspruch 1, worin der Kopfabschnitt eine im Wesentlichen planare Deckfläche des Kerns bildet und senkrecht zu der Richtung verläuft, die von jedem der beiden Beinabschnitte erzeugt wird, wobei die Richtung der beiden Beinabschnitte senkrecht zur Richtung der beiden Fußabschnitte verläuft, wobei die beiden Fußabschnitte in einer gemeinsamen Bodenebene liegen, und worin die beiden Beinabschnitte eine ringförmige Rille im Kern bilden, die sich entlang der Deckfläche des Kerns öffnet.
24. Kern zur Verwendung in einem Näherungssensor, worin der Kern einen Abschnitt mit Omega-Gestalt umfasst, der einen Mittelteil, zwei Fußabschnitte auf einander gegenüberliegenden Seiten des Mittelteils und zwei Beinabschnitte aufweist, die sich zwischen einem der Fußabschnitte und dem Mittelteil erstrecken, worin der Kern aus einem hochpermeablen Material besteht.
25. Kern nach Anspruch 24, worin die Beinabschnitte länglich sind und sich in Querrichtung zum Mittelteil und zu den Fußabschnitten erstrecken.
26. Kern nach Anspruch 14, worin der Kern aus einem im Wesentlichen rechteckigen Element konstruiert ist, das eine Vielzahl im Wesentlichen rechteckiger Oberflächen aufweist, die den Mittelteil, Fußabschnitte und Beine bilden, die jeweils eine Ebene definieren, wobei die Ebene des Mittelteils im Wesentlichen senkrecht zur Ebene eines jeden der Beine verläuft, wobei die Ebene des Mittelteils im Wesentlichen parallel zur Ebene eines jeden der Fußabschnitte verläuft, wobei der erste und der zweite Fußabschnitt an das erste bzw. das zweite Bein angrenzen.
27. Kern nach Anspruch 24, worin der Kern eine Dicke von etwa 0,020 Zoll aufweist.
28. Kern nach Anspruch 24, worin der Mittelteil des Kerns eine Breite von etwa 0,370 Zoll und eine Länge von etwa 0,390 Zoll aufweist.
29. Kern nach Anspruch 24, worin die Beine in Nachbarschaft des Mittelteils eine erste Breite und vom Mittelteil entfernt eine zweite Breite aufweisen, die sich von der ersten Breite unterscheidet.
30. Kern nach Anspruch 24, worin die Beinabschnitte eine Länge von etwa 0,300 Zoll, eine erste Breite von etwa 0,370 Zoll, die sich etwa 0,050 Zoll vom Mittelteil aus erstreckt, und eine zweite Breite von etwa 0,292 Zoll aufweisen, die sich etwa 0,250 Zoll über die erste Breite hinaus erstreckt.
31. Kern nach Anspruch 24, worin die Breite des Mittelteils größer ist als die Breite der Beinabschnitte und der Fußabschnitte.
32. Kern nach Anspruch 24, worin der Mittelteil des Kerns einen Kalibrierungsbolzen umfasst, der durch ihn hindurch angeordnet ist.
33. Näherungssensor nach Anspruch 24, worin die Querschnittsgestalt des Kerns weiters zwei Schwanzabschnitte umfasst, worin sich jeder Schwanzabschnitt von einer Außenkante eines der beiden Fußabschnitte aus erstreckt und worin die Schwanzabschnitte senkrecht zu zwei Fußabschnitten verlaufen.
34. Kern nach Anspruch 24, worin der Mittelteil eine im Wesentlichen planare Deckfläche des Kerns bildet und senkrecht zu der Richtung verläuft, die von jedem der beiden Beinabschnitte erzeugt wird, wobei die Richtung der beiden Beinabschnitte senkrecht zur Richtung der beiden Fußabschnitte verläuft, wobei die beiden Fußabschnitte in einer gemeinsamen Bodenebene liegen, und worin die beiden Beinabschnitte eine Oberfläche definieren, die eine ringförmige Rille im Kern bildet, die sich von der Deckfläche des Kerns aus öffnet.
35. Näherungssensor nach Anspruch 1, weiters umfassend:
- einen Kalibrierungsbolzen, der durch eine Öffnung im Mittelteil des Kerns hindurch angeordnet ist, worin der Kalibrierungsbolzen der ersten Abfühlschule und dem Kern operativ zugeordnet ist, so dass der Kalibrierungsbolzen ein elektrisches Signal beeinflusst, dass von der ersten Abfühlschule gemessen wird.

36. Näherungssensor nach Anspruch 35, worin der Kalibrierungsbolzen aus einem hochpermeablen Material besteht.

37. Näherungssensor nach Anspruch 35, worin der Kalibrierungsbolzen aus einem Material besteht, das aus der aus Weicheisen, Gusseisen und Transformator-Strahl bestehenden Gruppe ausgewählt ist.

38. Näherungssensor nach Anspruch 35, worin der Kalibrierungsbolzen aus einem Material besteht, das eine relative Permeabilität größer oder gleich 90 aufweist.

39. Näherungssensor nach Anspruch 35, worin die Position des Kalibrierungsbolzens in Bezug auf den Mittelteil eingestellt werden kann, so dass ein induktiver Blindwiderstandswert verändert wird, der von der ersten Abfühlpule gemessen wird, die um den Kern herum angeordnet ist.

40. Näherungssensor nach Anspruch 35, worin der Kalibrierungsbolzen eine Gewindeschraube ist.

41. Näherungssensor nach Anspruch 35, der weiters eine Schaltung umfasst, die mit der Abfühlpule gekoppelt ist, um ein Objekt abzufühlen, das sich in einem Abfühlbereich in Nachbarschaft des Kerns befindet.

42. Näherungssensor nach Anspruch 41, worin die Schaltung auch eine Abfühlpule mit Energie beaufschlagt, um den Abfühlbereich des Kerns zu schaffen.

43. Näherungssensor nach Anspruch 35, worin der Kern eine Dicke von etwa 0,020 Zoll aufweist.

44. Näherungssensor nach Anspruch 35, worin die Beine in Nachbarschaft des Mittelteils eine erste Breite und vom Mittelteil entfernt eine zweite Breite aufweisen, die sich von der ersten Breite unterscheidet.

45. Näherungssensor nach Anspruch 35, worin die Beine eine Länge von etwa 0,300 Zoll, eine erste Breite von etwa 0,370 Zoll, die sich etwa 0,050 Zoll vom Mittelteil aus erstreckt, und eine zweite Breite von etwa 0,292 Zoll aufweisen, die sich etwa 0,250 Zoll über die erste Breite hinaus erstreckt.

46. Näherungssensor, umfassend:

ein Element mit einer Deckfläche, einer Bodenfläche und einer Seitenfläche, das eine Breite zwischen der Deck- und der Bodenfläche des Elements aufweist, worin die Deckfläche im Allgemeinen planar ist und worin das Element ei-

nen Hohlraum definiert, der sich von der Deckfläche aus in das Element erstreckt, worin ein Abschnitt des Elements einen Mittelteil entlang der Deckfläche des Elements, zwei Fußabschnitte an einander gegenüberliegenden Seiten des Mittelteils und zwei Beine umfasst, worin sich jedes der beiden Beine zwischen dem Mittelteil und einem Fußabschnitt erstreckt, worin die Fußabschnitte und die Beine die Bodenfläche bzw. die Innenfläche des Hohlraums bilden, worin die Deck- und die Bodenfläche eine Dicke aufweisen, die kleiner oder gleich 0,06 Zoll ist, und worin das Element aus einem hochpermeablen Material besteht;

eine Abfühlpule, die im Hohlraum angeordnet ist, um Magnetfluss-Kommunikation zwischen der Abfühlpule und dem Kern zuzulassen; und

eine Schaltung, die mit der Abfühlpule gekoppelt ist, um ein Objekt abzufühlen, das sich in einem Abfühlbereich in Nachbarschaft zu dem Element befindet, worin das Element und die Schaltung eine solche Konfiguration und Anordnung aufweisen, dass sie das Vorhandensein ferromagnetischer, nicht-permeablen und magnetischer Ziele detektieren.

47. Näherungssensor nach Anspruch 46, worin die Deck- und die Bodenfläche des Elements eine Dicke unter 0,06 Zoll und über oder gleich 0,005 Zoll aufweisen.

48. Näherungssensor nach Anspruch 46, worin das Element aus einem permeablen Material konstruiert ist.

49. Näherungssensor nach Anspruch 46, worin das Element eine im Allgemeinen zylindrische Gestalt aufweist.

50. Näherungssensor nach Anspruch 46, worin die Breite des Elements im Bereich von 0,2 bis 5 Zoll liegt.

51. Näherungssensor nach Anspruch 46, worin die Deckfläche vom Außendurchmesser des Elements radial nach außen beabstandet ist.

52. Verfahren zum Detektieren des Vorhandenseins eines Objektes, das umfasst:

das Bereitstellen eines Kerns mit einem Querschnitt mit Omega-Gestalt, der einen Mittelteil, zwei Fußabschnitte an einander gegenüberliegenden Seiten des Mittelteils und zwei Beine umfasst, die sich jeweils zwischen einem der Fußabschnitte und dem Mittelteil erstrecken;

das Bereitstellen zumindest einer Abfühlspeule, die um den Kern herum angeordnet ist; und

das Messen des induktiven Blindwiderstands über die Abfühlspeule, und wenn der induktive Blindwiderstand über einen vorbestimmten Bereich variiert, das Erzeugen eines Signals, um das Vorhandensein des Objekts anzuzeigen.

53. Verfahren nach Anspruch 52, worin die Beinabschnitte länglich sind und sich in Querrichtung zum Mittelabschnitt und den Fußabschnitten erstrecken.

54. Verfahren nach Anspruch 52, das weiters das Bereitstellen einer zweiten Abfühlspeule umfasst, die um den Kern herum angeordnet ist.

55. Verfahren nach Anspruch 52, worin das Objekt ein magnetisches Material umfasst.

56. Verfahren nach Anspruch 52, worin das Objekt ein ferromagnetisches Material umfasst.

57. Verfahren nach Anspruch 52, worin das Objekt ein leitendes Material umfasst.

Revendications

1. Détecteur de proximité, comprenant :

un noyau présentant une section incluant une partie centrale, deux portions de pied sur des côtés opposés de la partie centrale et deux branches s'étendant chacune entre l'une des portions de pied et la partie centrale, où les deux branches sont positionnées sur des côtés opposés de la partie centrale ;

une première bobine de détection positionnée autour du noyau ; et

un circuit couplé à la première bobine de détection pour détecter un objet situé dans une région de détection adjacente au noyau, où le noyau et le circuit sont configurés et agencés pour détecter la présence de cibles ferromagnétiques, non-perméables et magnétiques.

2. Détecteur de proximité selon la revendication 1, où les branches sont oblongues et s'étendent transversalement à la partie centrale et aux portions de pied.

3. Détecteur de proximité selon la revendication 1, comprenant en outre une deuxième bobine de détection positionnée autour du noyau, où les première et seconde bobines de détection ont des tours enroulés autour des branches.

4. Détecteur de proximité selon la revendication 3, où le circuit excite également la bobine de détection pour créer la région de détection du noyau.

5. Détecteur de proximité selon la revendication 1, où le circuit comprend un oscillateur pour exciter la bobine de détection afin de créer la région de détection.

6. Détecteur de proximité selon la revendication 5, où l'oscillateur comporte un circuit oscillateur de suppression des courants de Foucault.

7. Détecteur de proximité selon la revendication 5, où l'oscillateur comprend un circuit entièrement métallique de détection des pertes par courants de Foucault.

8. Capteur de proximité selon la revendication 1, où le noyau est réalisé en un matériau perméable.

9. Détecteur de proximité selon la revendication 1, où le noyau est réalisé par un élément sensiblement rectangulaire présentant plusieurs surfaces sensiblement rectangulaires formant la partie centrale, les portions de pied et les branches, chacune définissant un plan, le plan de la partie centrale étant sensiblement perpendiculaire au plan de chacune des branches, le plan de la partie centrale étant sensiblement parallèle au plan de chacune des portions de pied, les première et seconde portions de pied étant adjacentes aux première et seconde branches, respectivement.

10. Détecteur de proximité selon la revendication 8, où la largeur de la partie centrale du noyau est plus grande que la largeur des deux portions de branche et des portions de pied.

11. Détecteur de proximité selon la revendication 1, où le noyau a une épaisseur d'environ 0,020 pouce.

12. Détecteur de proximité selon la revendication 1, où la partie centrale du noyau a une largeur d'environ 0,370 pouce et une longueur d'environ 0,390 pouce.

13. Détecteur de proximité selon la revendication 1, où les branches ont une première largeur adjacente à la partie centrale et une seconde largeur, différente de la première largeur, éloignée de la partie centrale.

14. Détecteur de proximité selon la revendication 1, où les portions de branche ont une longueur d'environ 0,300 pouce, une première largeur d'environ 0,370 pouce s'étendant approximativement sur 0,050 pouce de la partie centrale, et une seconde largeur

d'environ 0,292 pouce s'étendant approximativement sur 0,250 pouce au-delà de la première largeur.

15. Détecteur de proximité selon la revendication 1, comprenant en outre un boîtier supportant la bobine de détection et le noyau. 5
16. Détecteur de proximité selon la revendication 1, où la portion centrale du noyau comprend un boulon de calibrage. 10
17. Détecteur de proximité selon la revendication 16, où le boulon de calibrage est réalisé en un matériau hautement perméable. 15
18. Détecteur de proximité selon la revendication 16, où le boulon de calibrage est réalisé en un matériau sélectionné dans le groupe constitué de fer mou, de fer coulé et d'acier de transformation. 20
19. Détecteur de proximité selon la revendication 16, où le boulon de calibrage est réalisé en un matériau d'une perméabilité relative égale ou supérieure à 90. 25
20. Détecteur de proximité selon la revendication 16, où la position du boulon de calibrage relativement au restant de la partie centrale est ajustable pour changer un niveau d'inductance qui est mesuré par la première bobine de détection positionnée autour du noyau. 30
21. Détecteur de proximité selon la revendication 16, où le boulon de calibrage est une vis filetée. 35
22. Détecteur de proximité selon la revendication 1, où la forme en section transversale du noyau comprend en outre deux portions de queue, où chaque portion de queue s'étend à partir d'un bord extérieur d'une des deux portions de pied, et où les portions de queue sont perpendiculaires aux deux portions de pied. 40
23. Détecteur de proximité selon la revendication 1, où la portion de tête forme une surface supérieure sensiblement plane du noyau et est perpendiculaire à la direction créée par chacune des deux portions de branche, la direction des deux portions de branche étant perpendiculaire à la direction des deux portions de pied, les deux portions de pied se situant dans un plan de surface inférieur commun, et où les deux portions de branche forment une rainure annulaire dans le noyau qui s'ouvre le long de la surface supérieure du noyau. 45 50
24. Noyau pour utilisation dans un détecteur de proximité, où le noyau comprend une section d'une for-

me oméga présentant une partie centrale, deux portions de pied sur des côtés opposés de la partie centrale et deux portions de branche s'étendant chacune entre l'une des portions de pied et la partie centrale, où le noyau est réalisé en un matériau hautement perméable.

25. Noyau selon la revendication 24, où les portions de branche sont oblongues et s'étendent transversalement à la partie centrale et aux portions de pied.
26. Noyau selon la revendication 24, où le noyau est réalisé en un élément sensiblement rectangulaire présentant plusieurs surfaces sensiblement rectangulaires formant la partie centrale, les portions de pied et les branches, chacune définissant un plan, le plan de la partie centrale étant sensiblement perpendiculaire au plan de chacune des branches, le plan de la partie centrale étant sensiblement parallèle au plan de chacune des portions de pied, les première et seconde portions de pied étant adjacentes aux première et seconde branches, respectivement.
27. Noyau selon la revendication 24, où le noyau a une épaisseur d'environ 0,020 pouce. 25
28. Noyau selon la revendication 24, où la partie centrale du noyau a une largeur d'environ 0,370 pouce et une longueur d'environ 0,390 pouce. 30
29. Noyau selon la revendication 24, où les branches ont une première largeur adjacente à la partie centrale et une seconde largeur, différente de la première largeur, éloignée de la partie centrale.
30. Noyau selon la revendication 24, où les portions de branche ont une longueur d'environ 0,300 pouce, une première largeur d'environ 0,370 pouce s'étendant sur environ 0,050 pouce depuis la partie centrale, et une seconde largeur d'environ 0,292 pouce s'étendant sur environ 0,250 pouce au-delà de la première largeur.
31. Noyau selon la revendication 24, où la largeur de la partie centrale est plus grande que la largeur des portions de branche et des portions de pied.
32. Noyau selon la revendication 24, où la partie centrale du noyau comprend un boulon de calibrage positionné à travers celle-ci.
33. Détecteur de proximité selon la revendication 24, où la forme en section transversale du noyau comprend en outre deux portions de queue, où chaque portion de queue s'étend d'un bord externe d'une des deux portions de pied, et où les portions de queue sont perpendiculaires aux deux portions de

pied.

34. Noyau selon la revendication 24, où la partie centrale forme une surface supérieure sensiblement plane du noyau et est perpendiculaire à la direction créée par chacune des deux portions de branche, la direction des deux portions de branche étant perpendiculaire à la direction des deux portions de pied, les deux portions de pied se situant dans un plan de surface inférieure commun, et où les deux portions de branche définissent une surface qui forme une rainure annulaire dans le noyau qui s'ouvre depuis la surface supérieure du noyau. 5 10
35. Détecteur de proximité selon la revendication 1, comprenant en outre : 15
- un boulon de calibrage positionné à travers une ouverture dans la partie centrale du noyau, où le boulon de calibrage est fonctionnellement associé à la première bobine de détection et au noyau de façon que le boulon de calibrage ait une influence sur un signal électrique mesuré par la première bobine de détection. 20 25
36. Détecteur de proximité selon la revendication 35, où le boulon de calibrage est réalisé en un matériau hautement perméable.
37. Détecteur de proximité selon la revendication 35, où le boulon de calibrage est réalisé en un matériau sélectionné dans le groupe constitué de fer mou, de fer coulé et d'acier de transformation. 30
38. Détecteur de proximité selon la revendication 35, où le boulon de calibrage est réalisé en un matériau d'une perméabilité relative égale ou supérieure à 90. 35
39. Détecteur de proximité selon la revendication 35, où la position du boulon de calibrage relativement à la partie centrale est ajustable pour changer un niveau d'inductance qui est mesuré par la première bobine de détection positionnée autour du noyau. 40 45
40. Détecteur de proximité selon la revendication 35, où le boulon de calibrage est une vis filetée.
41. Détecteur de proximité selon la revendication 35, comprenant en outre un circuit couplé à la bobine de détection pour détecter un objet situé dans une région de détection adjacente au noyau. 50
42. Détecteur de proximité selon la revendication 41, où le circuit excite également la bobine de détection pour créer une région de détection du noyau. 55
43. Détecteur de proximité selon la revendication 35,

où le noyau a une épaisseur d'environ 0,020 pouce.

44. Détecteur de proximité selon la revendication 35, où les branches ont une première largeur adjacente à la partie centrale et une seconde largeur, différente de la première largeur, à distance de la partie centrale.
45. Détecteur de proximité selon la revendication 35, où les branches ont une longueur d'environ 0,300 pouce, une première largeur d'environ 0,370 pouce s'étendant sur environ 0,050 pouce à partir de la partie centrale et une seconde largeur d'environ 0,292 pouce s'étendant sur environ 0,250 pouce au-delà de la première largeur.
46. Détecteur de proximité, comprenant :
- un élément présentant une surface supérieure, une surface inférieure et une surface latérale ayant une largeur entre les surfaces supérieure et inférieure de l'élément, où la surface supérieure est généralement plane, et où l'élément définit une cavité qui s'étend dans l'élément depuis la surface supérieure, où une section de l'élément comporte une partie centrale le long de la surface supérieure de l'élément, deux positions de pied sur des côtés opposés de la partie centrale et deux branches, où chacune des deux branches s'étend entre la partie centrale et une portion de pied, où les portions de pied et les branches forment respectivement la surface inférieure et la surface intérieure de la cavité, où les surfaces supérieure et inférieure ont une épaisseur inférieure ou égale à 0,06 pouce, et où l'élément est réalisé en un matériau hautement perméable ;
- une bobine de détection positionnée dans la cavité pour permettre une communication de flux magnétique entre la bobine de détection et le noyau ; et
- un circuit couplé à la bobine de détection pour détecter un objet situé dans une région de détection adjacente à l'élément, où l'élément et le circuit sont configurés et agencés pour détecter la présence de cibles ferromagnétiques, non-perméables et magnétiques.
47. Détecteur de proximité selon la revendication 46, où les surfaces supérieure et inférieure de l'élément ont une épaisseur inférieure à 0,06 pouce et supérieure ou égale à 0,005 pouce.
48. Détecteur de proximité selon la revendication 46, où l'élément est réalisé en un matériau perméable.

49. Détecteur de proximité selon la revendication 46, où l'élément a généralement une forme cylindrique.
50. Détecteur de proximité selon la revendication 46, où la largeur de l'élément se situe dans la plage de 0,2 à 5 pouces. 5
51. Détecteur de proximité selon la revendication 46, où la surface supérieure est espacée radialement vers l'extérieur du périmètre extérieur de l'élément. 10
52. Procédé de détection de la présence d'un objet qui comprend :
- réaliser un noyau ayant une section d'une forme oméga incluant une partie centrale, deux portions de pied sur les côtés opposés de la partie centrale et deux branches s'étendant chacune entre l'une des portions de pied et la partie centrale ; 15 20
- réaliser au moins une bobine de détection positionnée autour du noyau ; et
- mesurer l'inductance sur la bobine de détection, et si l'inductance varie sur une plage prédéterminée, produire un signal pour indiquer la présence de l'objet. 25
53. Procédé selon la revendication 52, où les portions de branche sont oblongues et s'étendent transversalement de la partie centrale et des portions de pied. 30
54. Procédé selon la revendication 52, comprenant en outre la réalisation d'une seconde bobine de détection positionnée autour du noyau. 35
55. Procédé selon la revendication 52, où l'objet comprend un matériau magnétique. 40
56. Procédé selon la revendication 52, où l'objet comprend un matériau ferromagnétique.
57. Procédé selon la revendication 52, où l'objet comprend un matériau conducteur. 45

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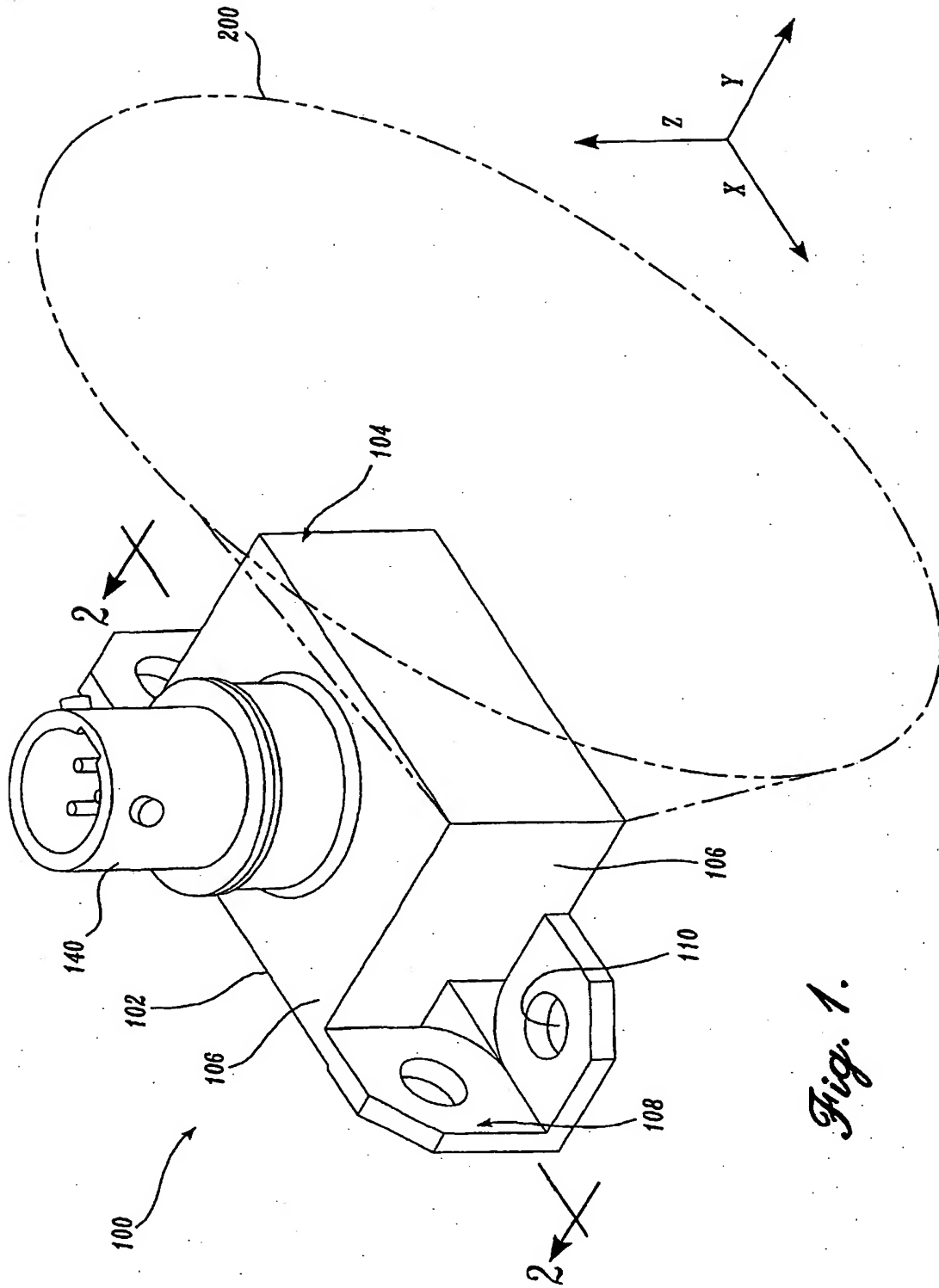


Fig. 1.

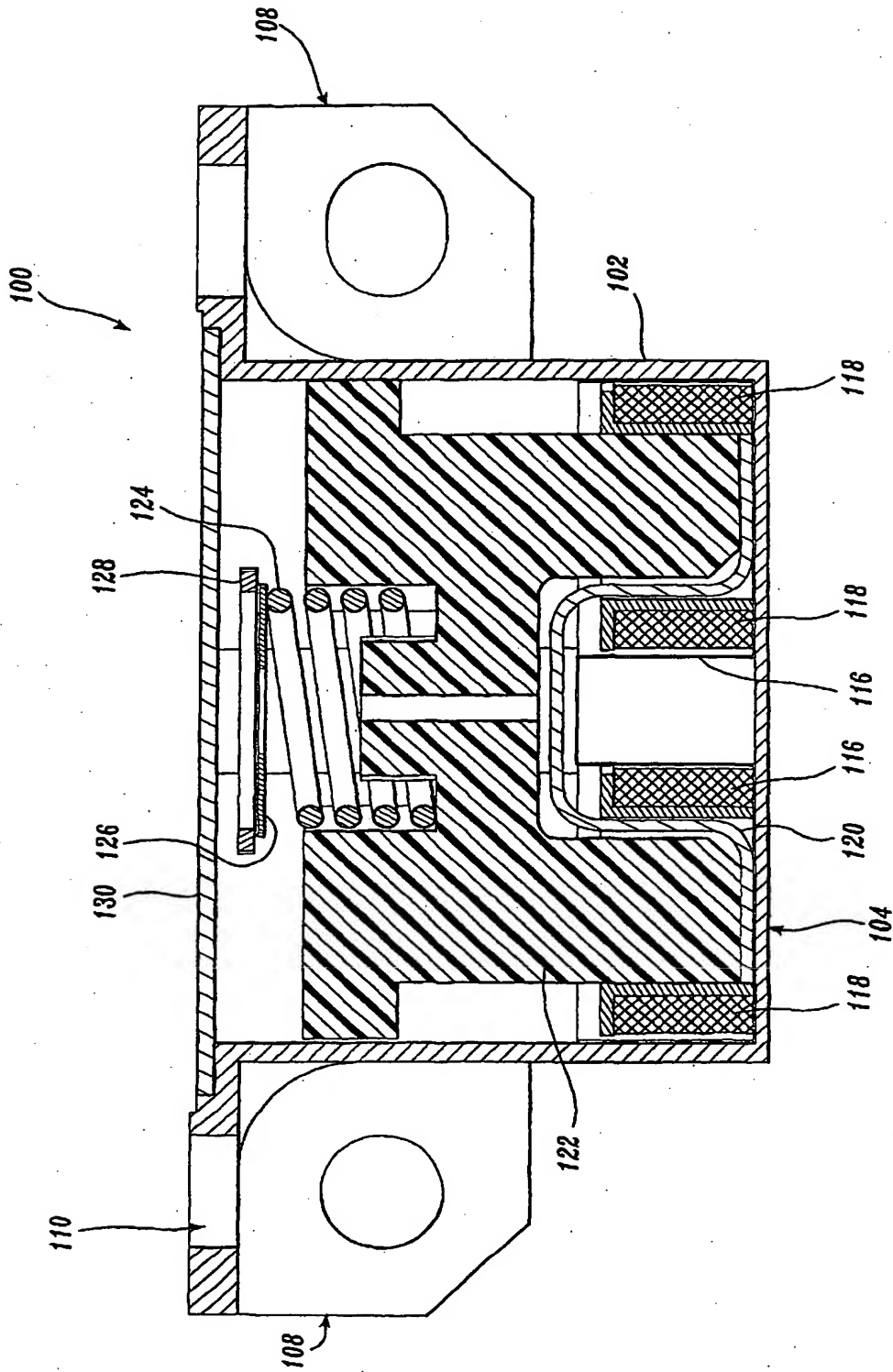


Fig. 2.

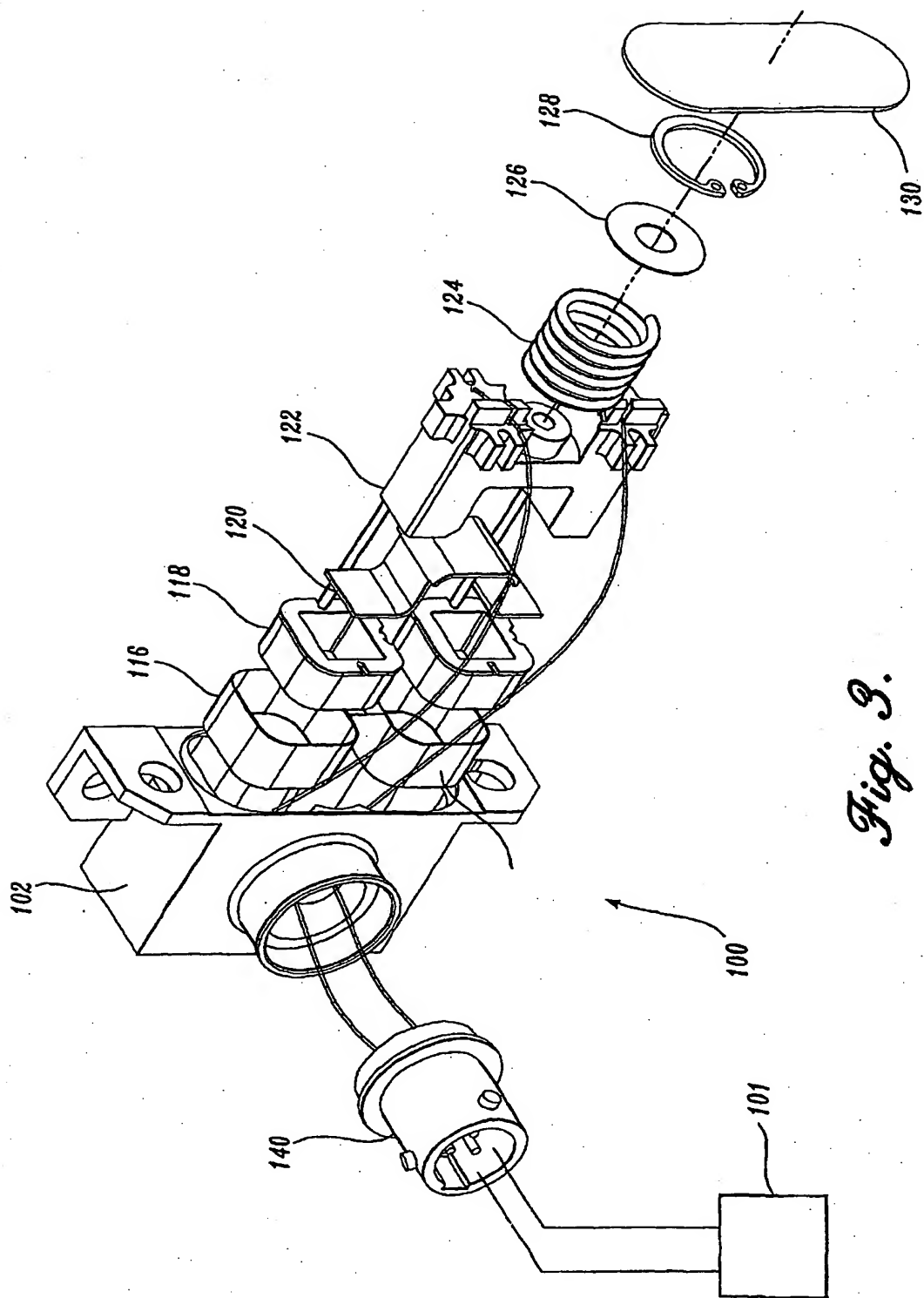


Fig. 3.

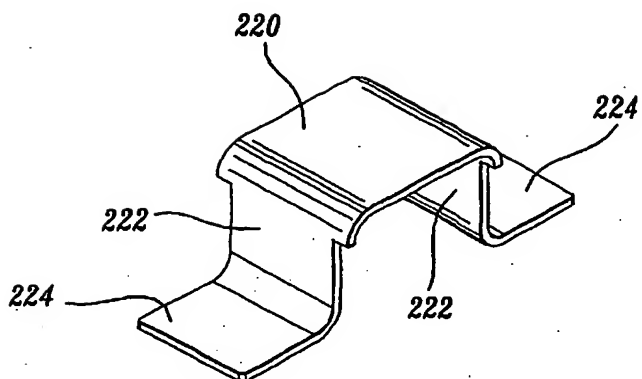


Fig. 4A

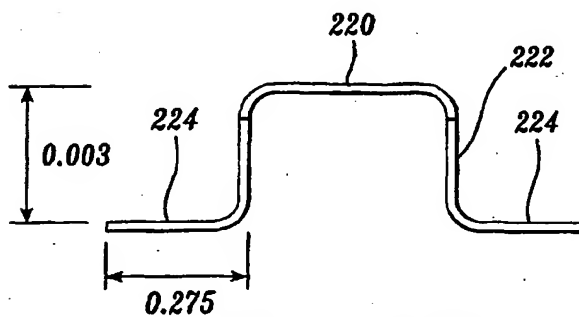


Fig. 4B.

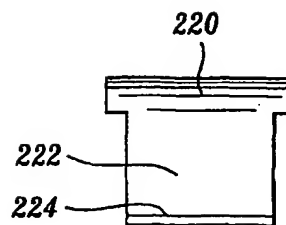


Fig. 4C.

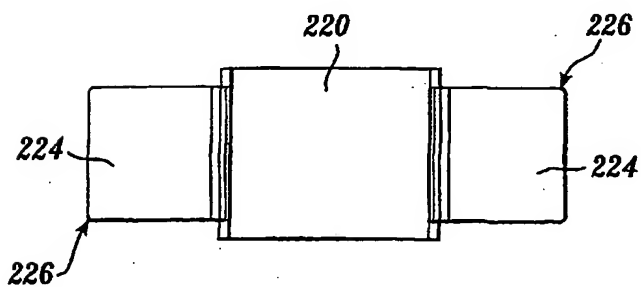


Fig. 4D.

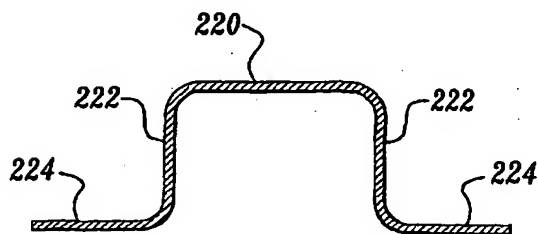


Fig. 4E.

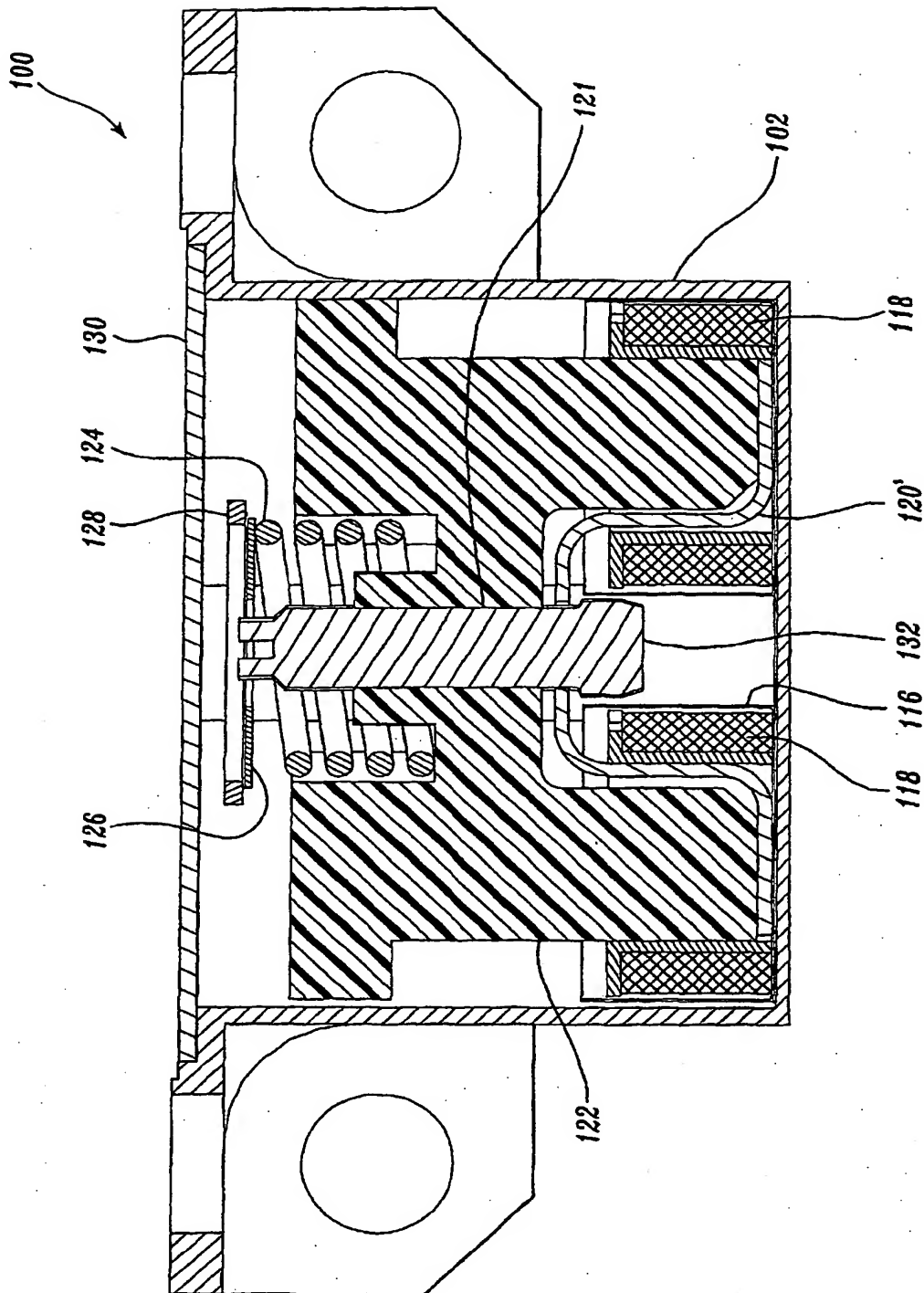


Fig. 5.

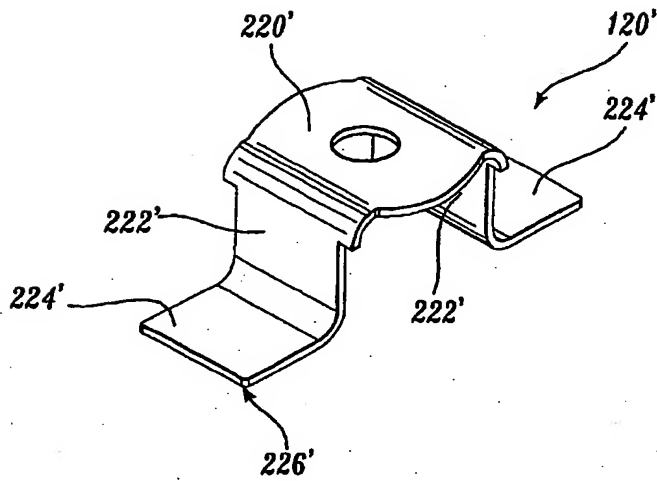


Fig. 6A.

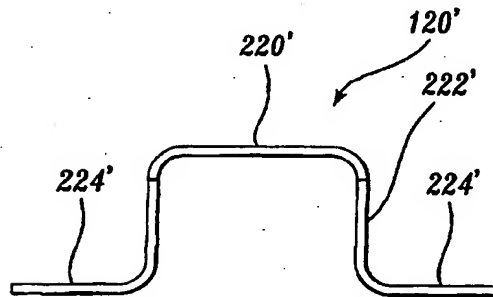


Fig. 6B.

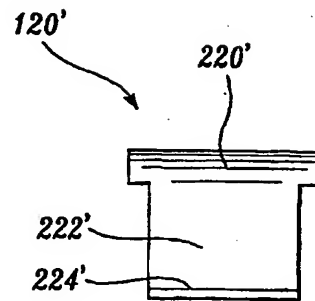


Fig. 6C.

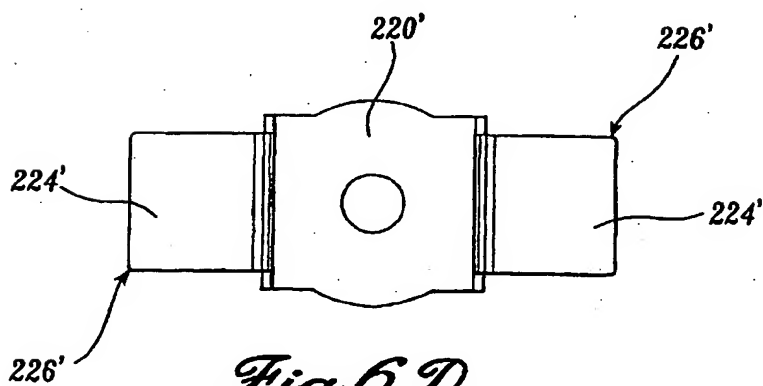


Fig. 6D.

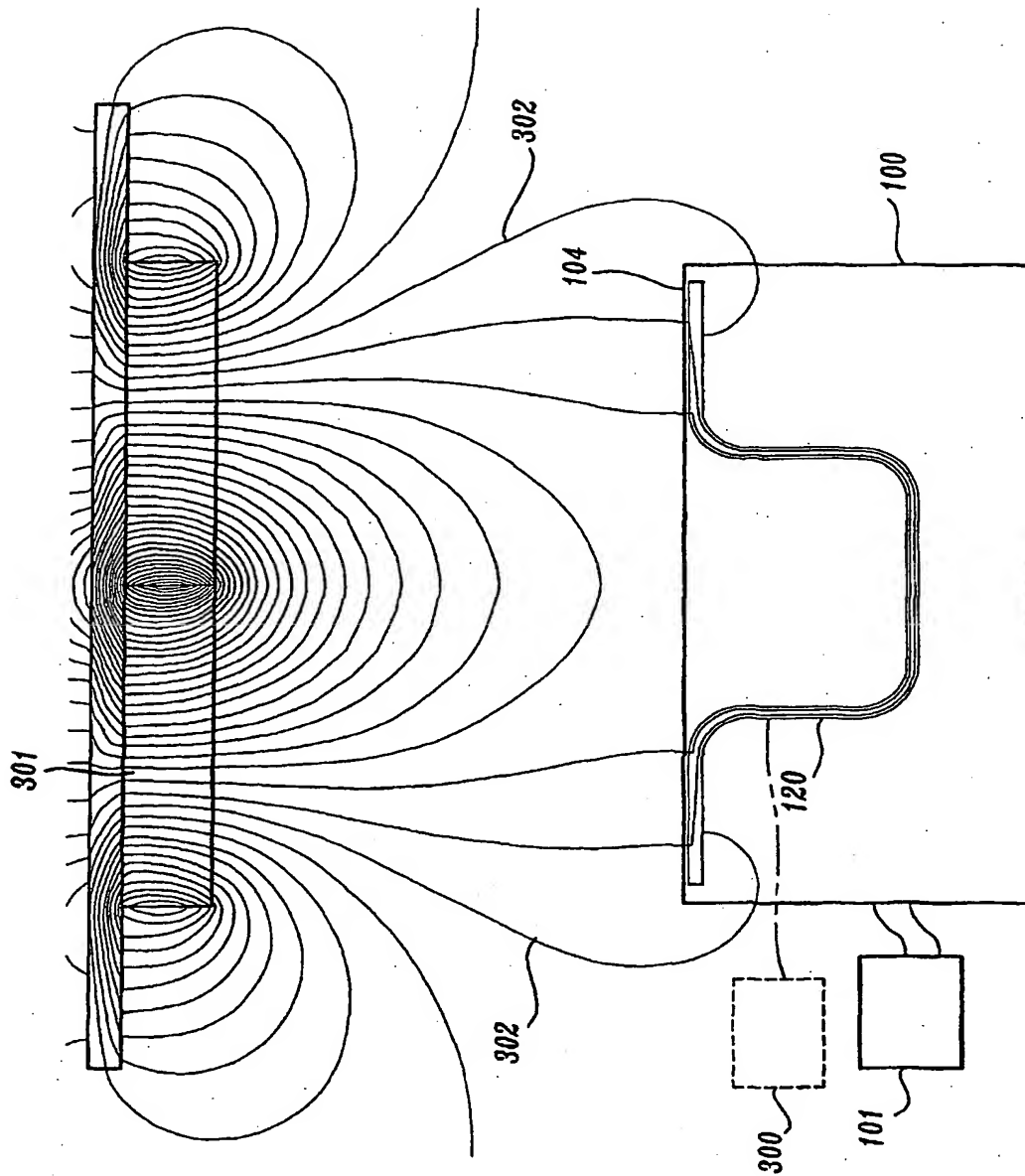


Fig. 7.

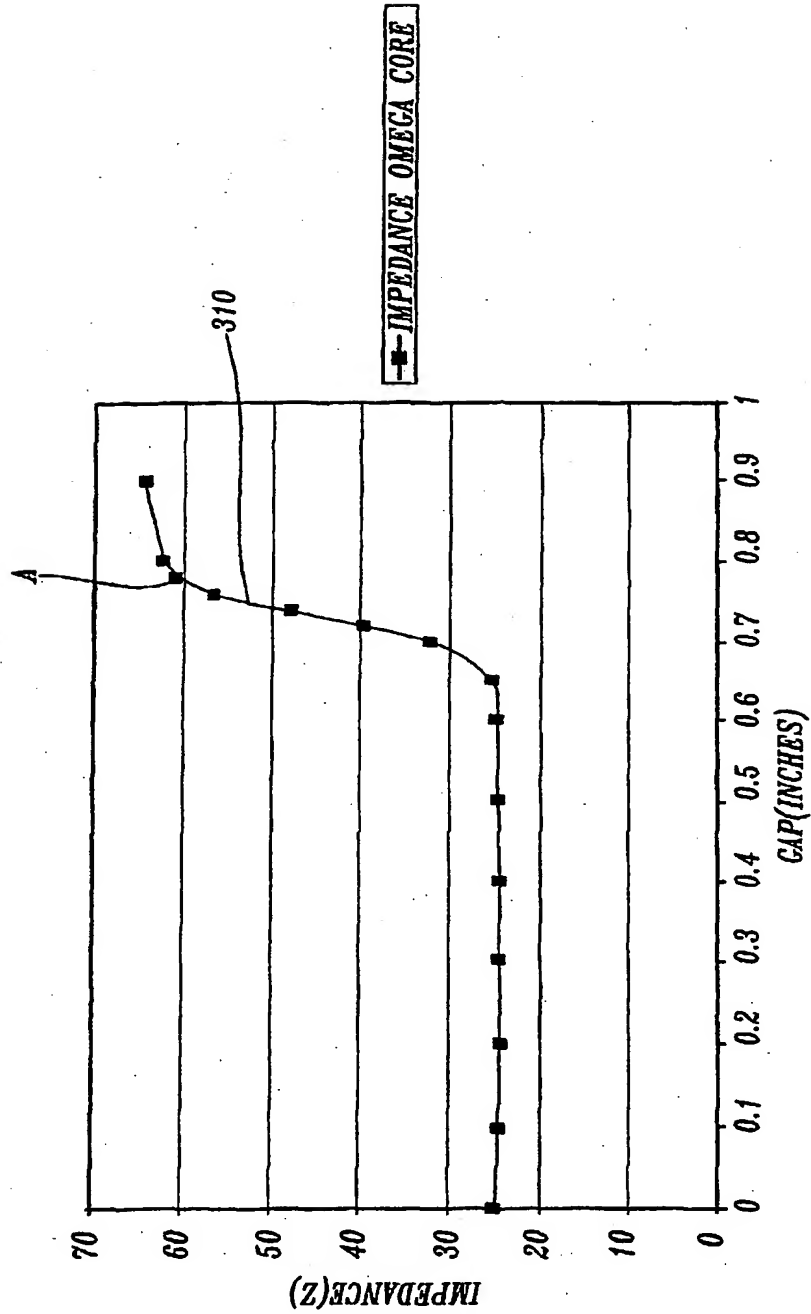


Fig. 8.

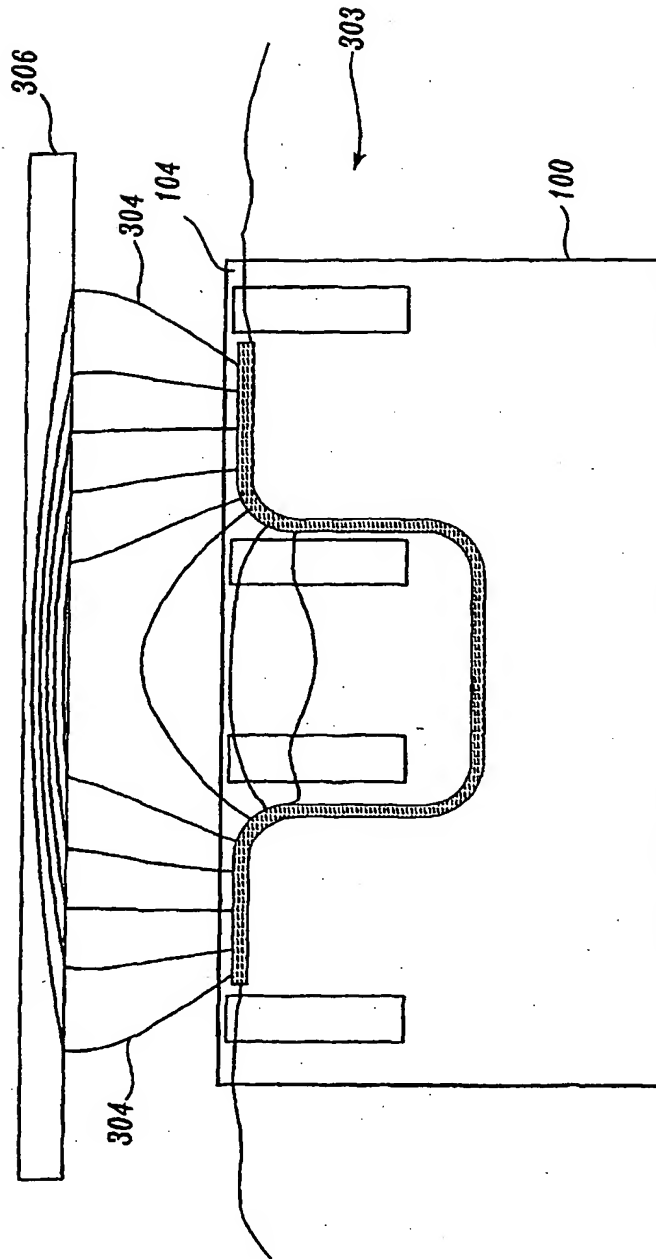


Fig. 9.

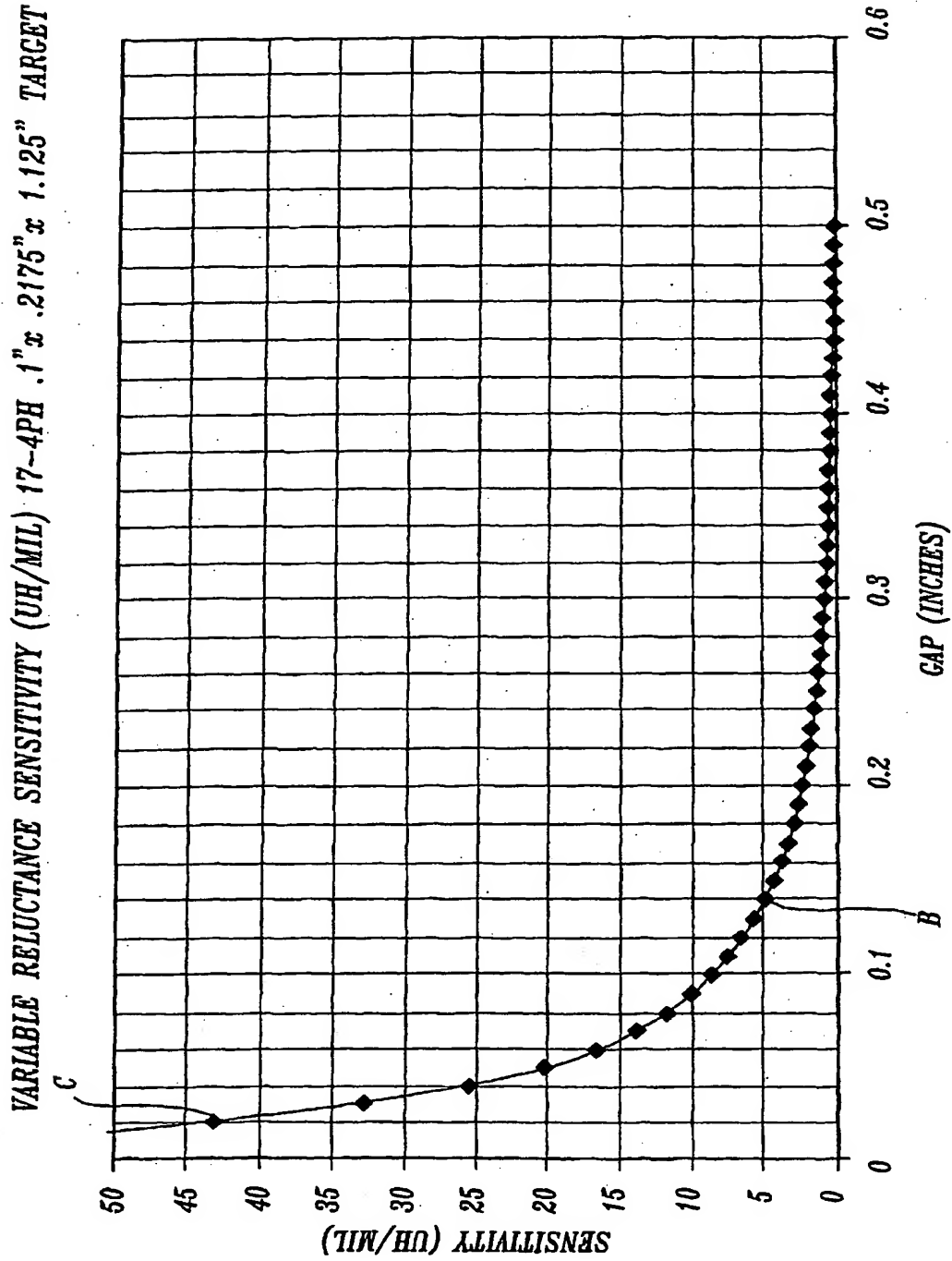


Fig. 10.

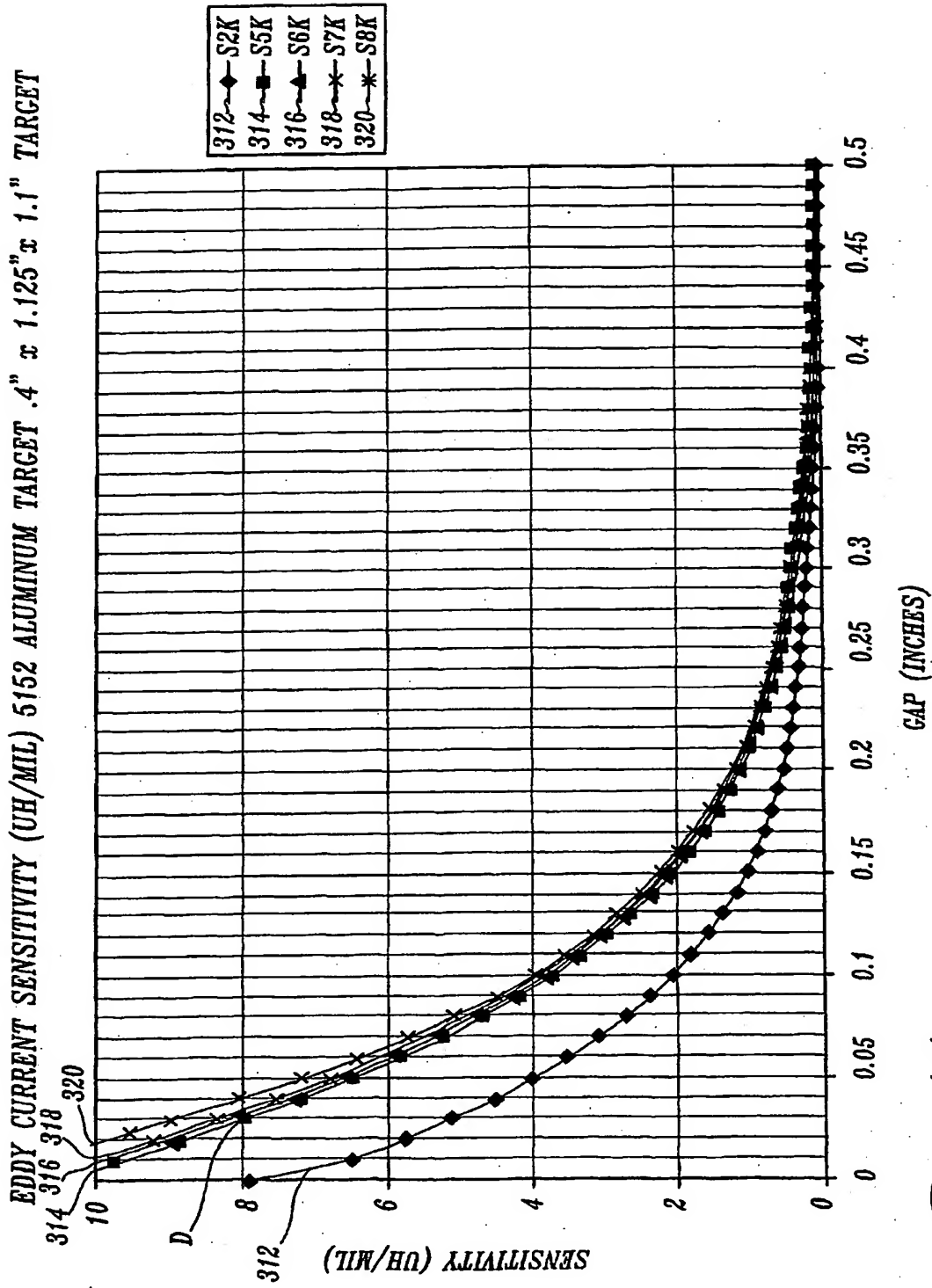


Fig. 11.

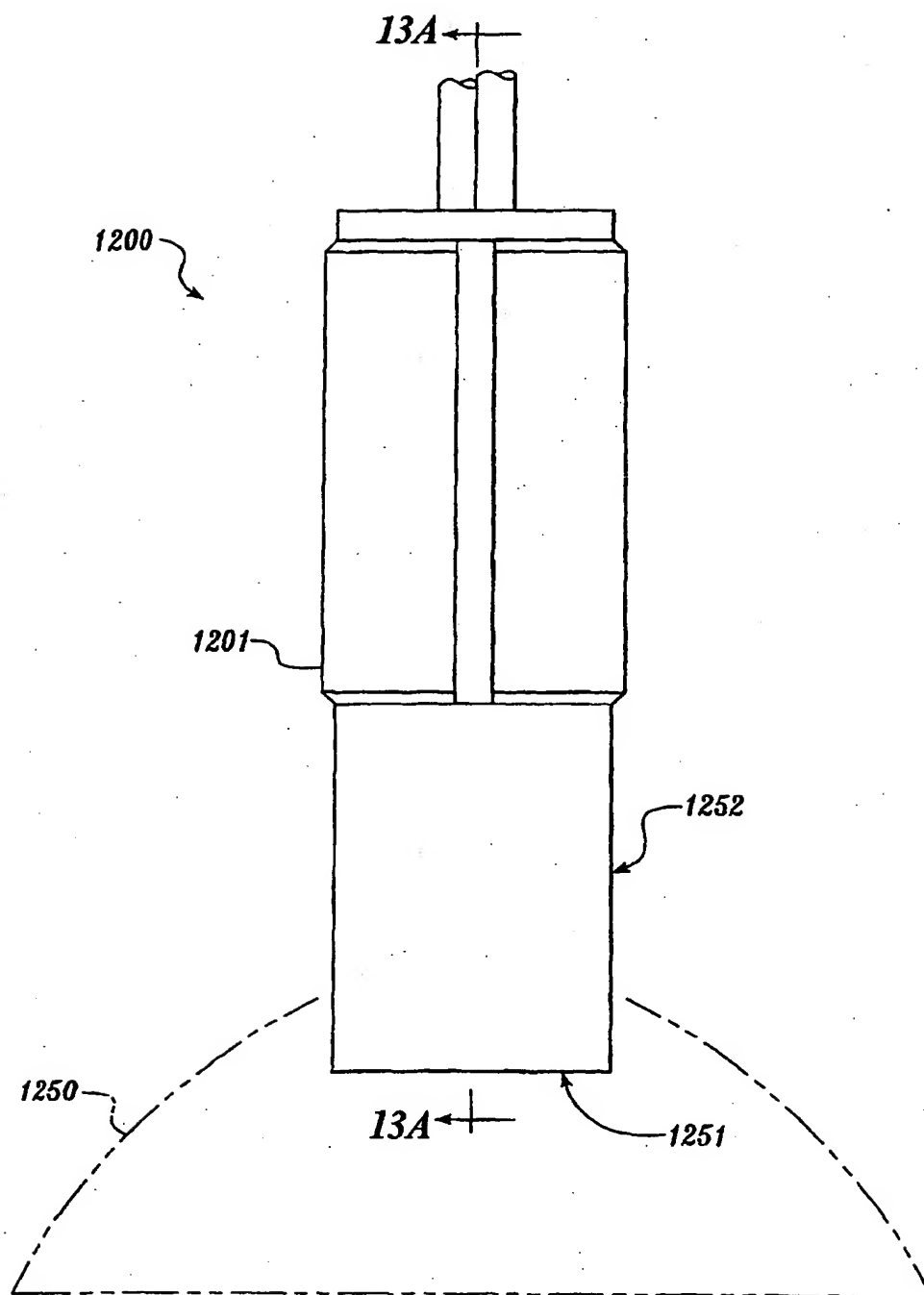


Fig. 12.

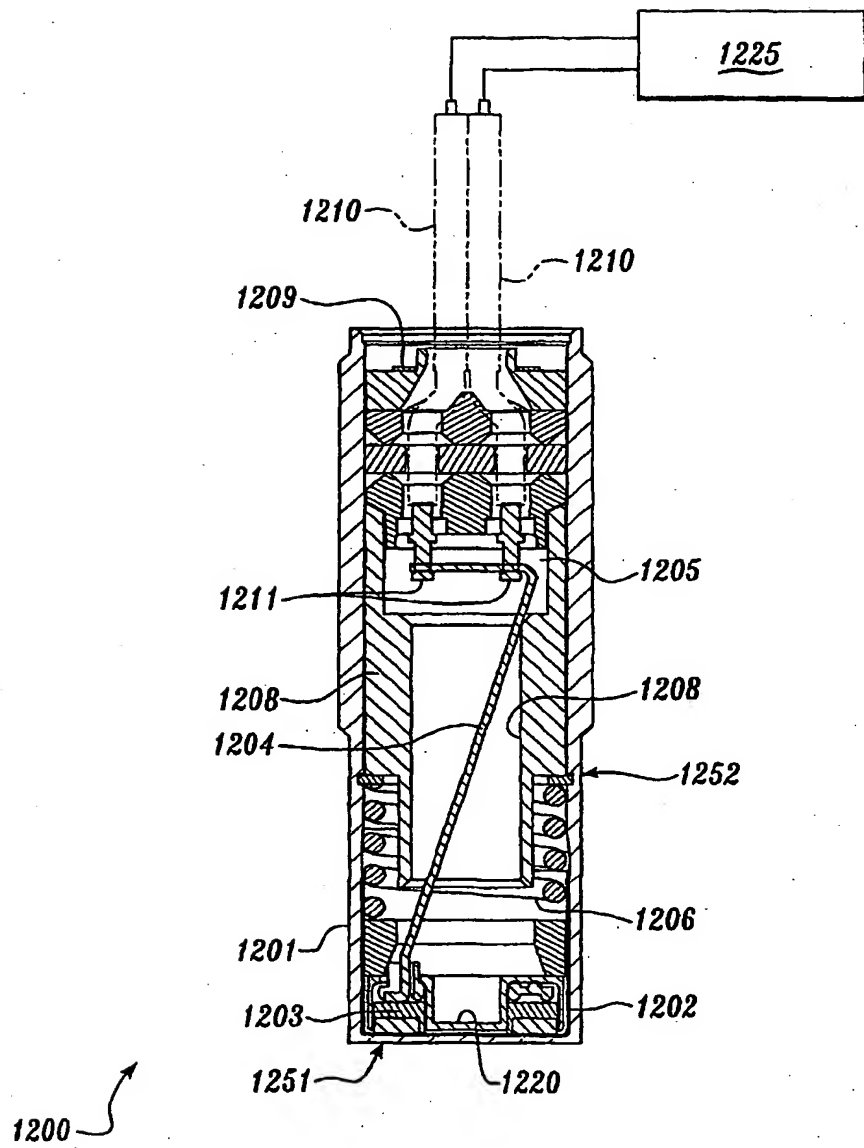
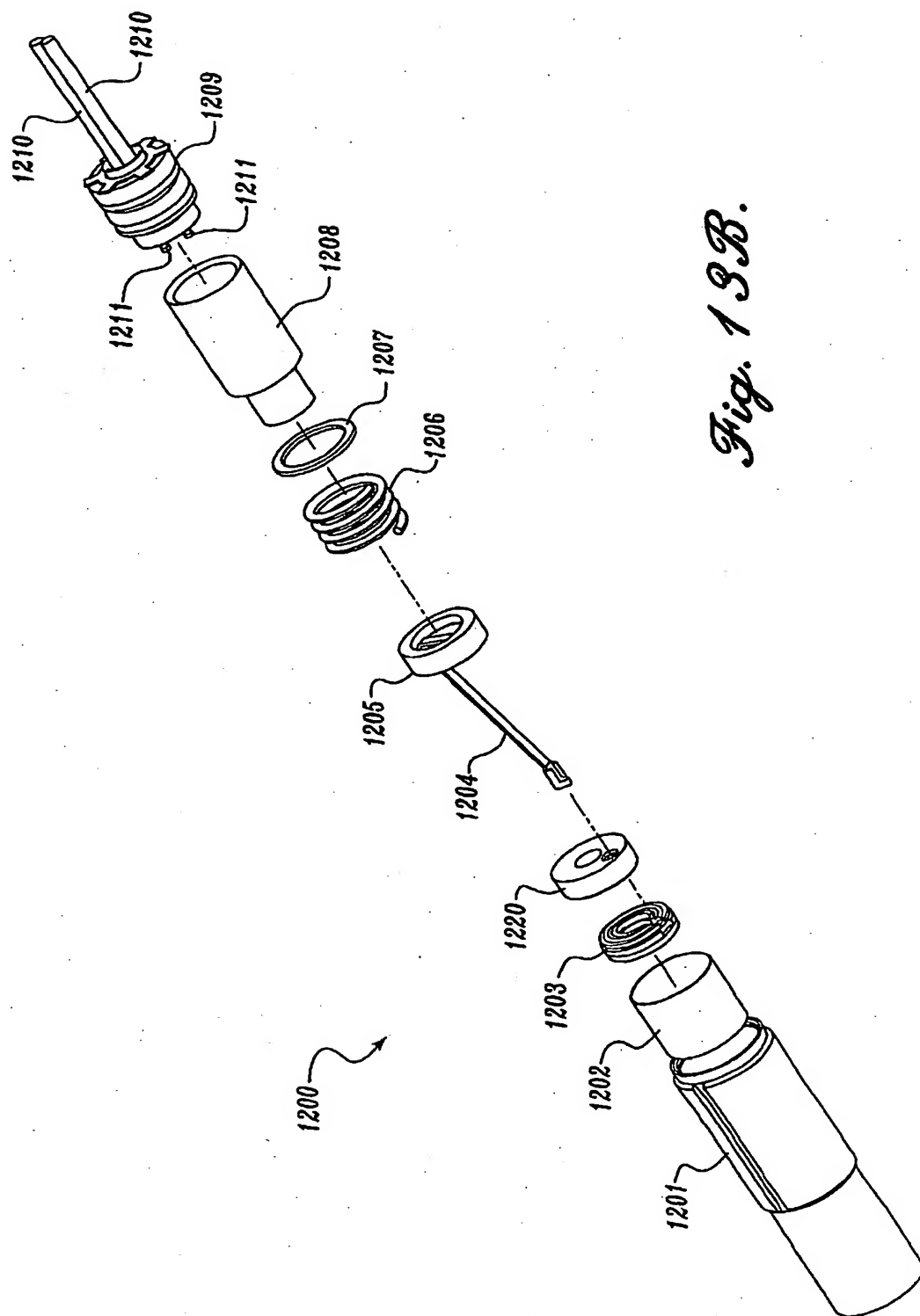


Fig. 13.A.



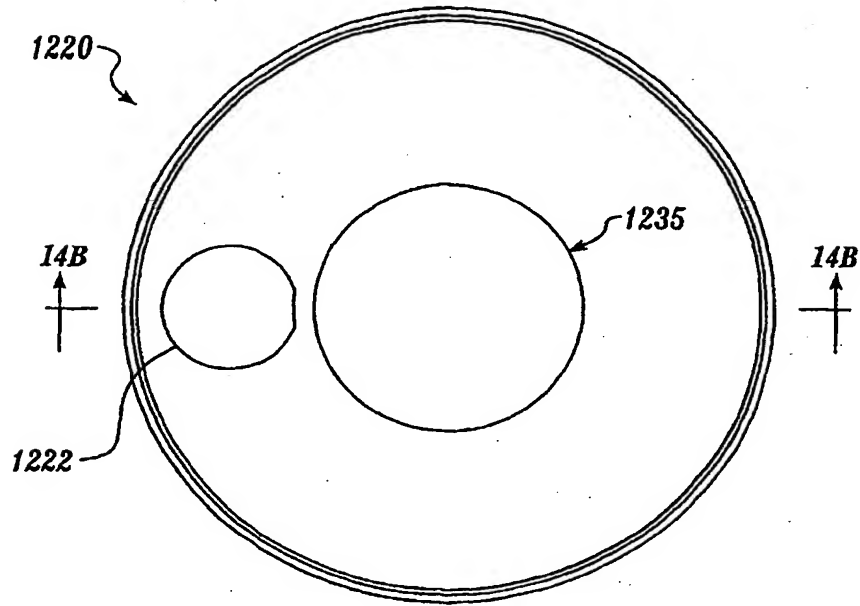


Fig. 14A.

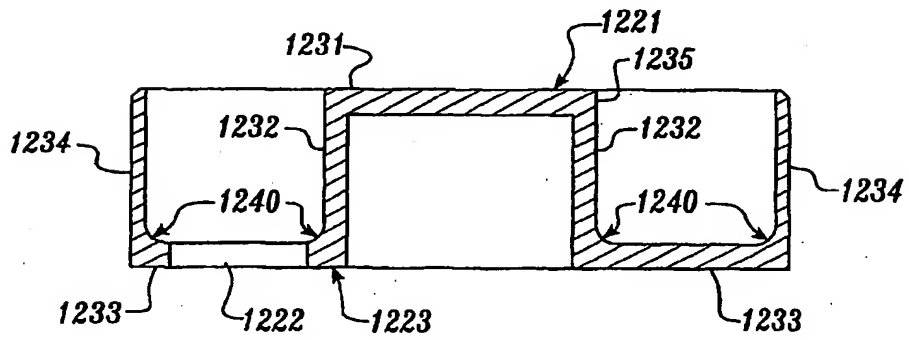


Fig. 14B.

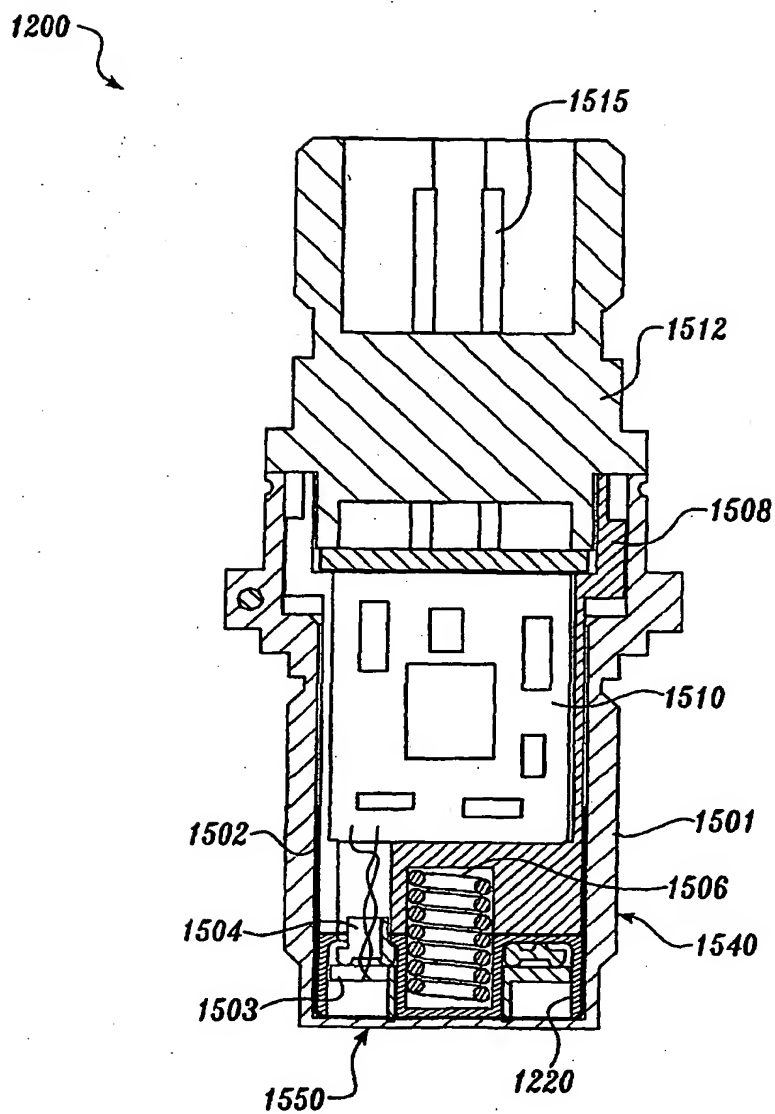


Fig. 15.A.

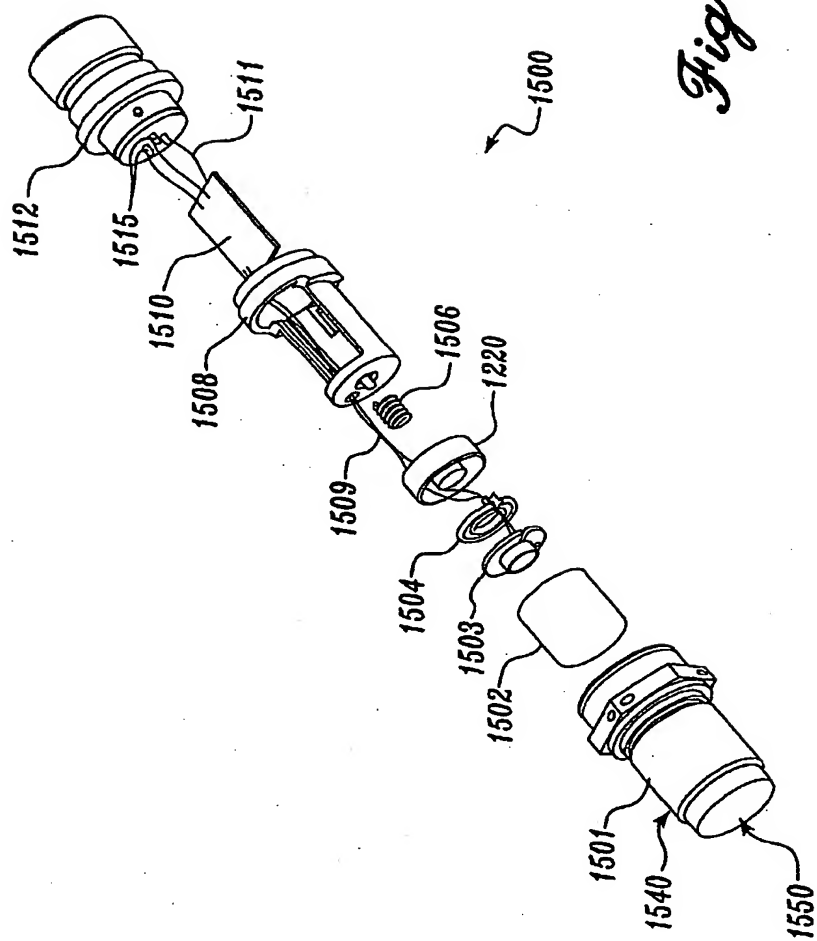


Fig. 15B.

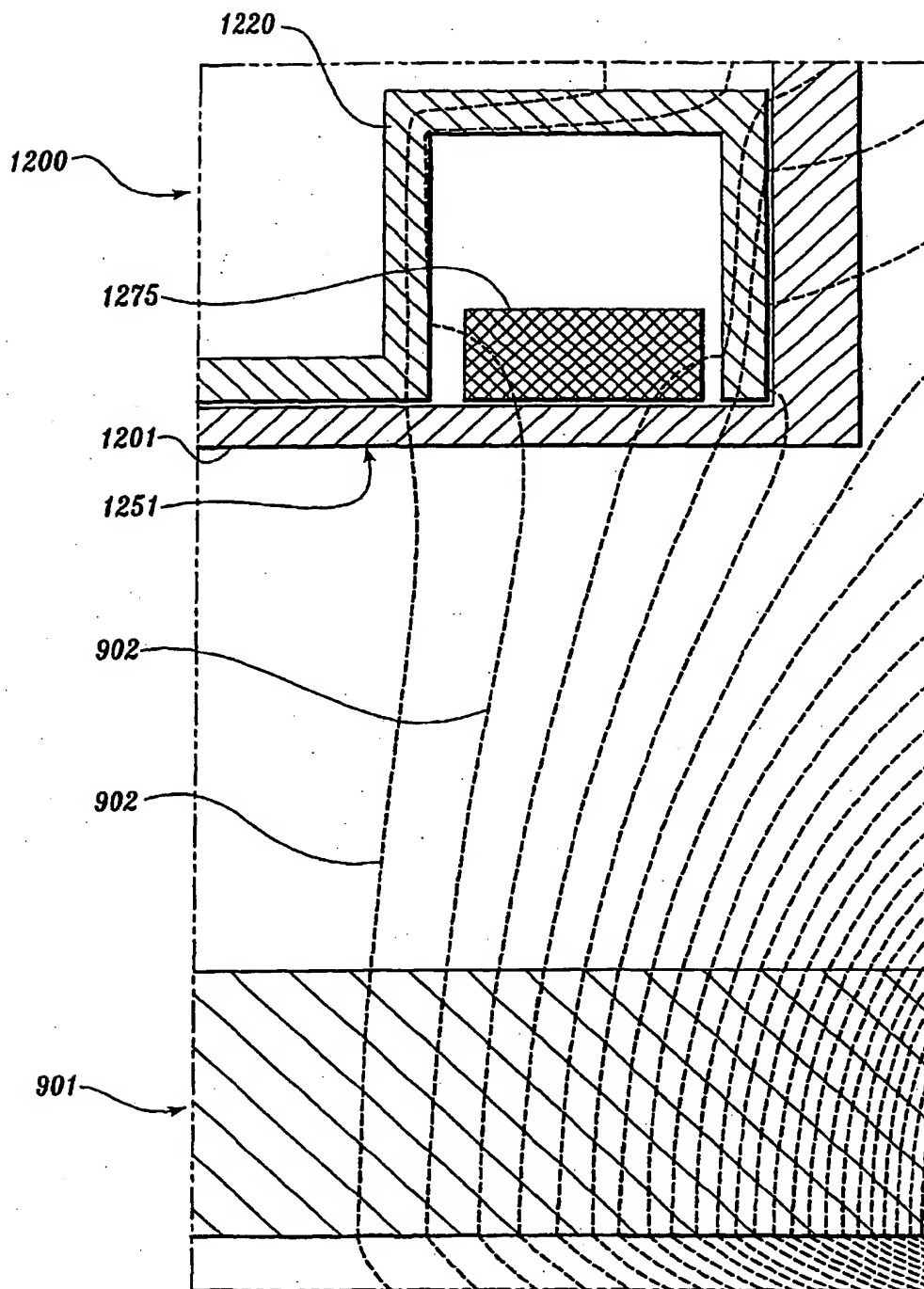


Fig. 16.

THIN CUP CORE WITH .75" DIAMETER x .124" MAGNET ON .75" DIAMETER X .05" 17-4

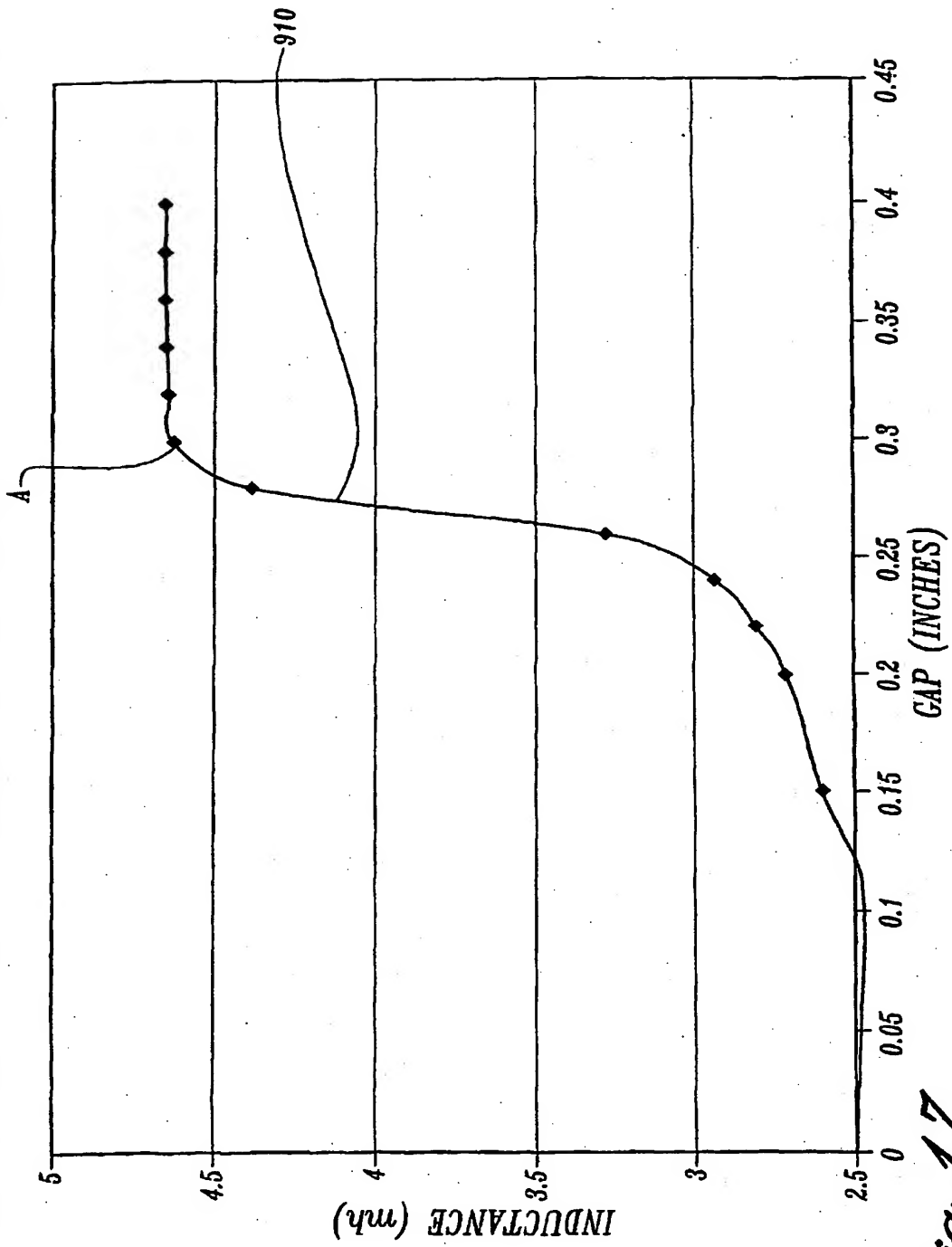


Fig. 17.

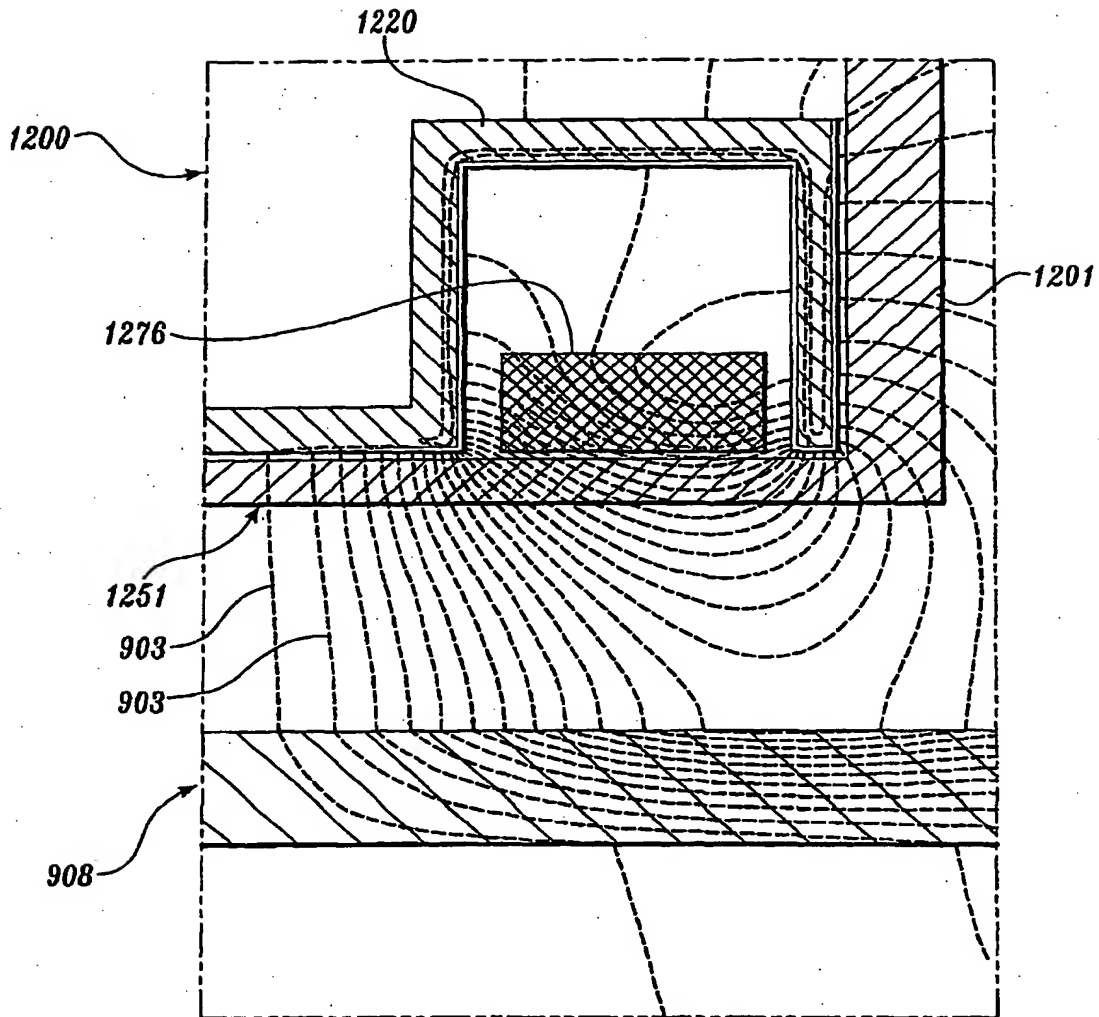


Fig. 18.

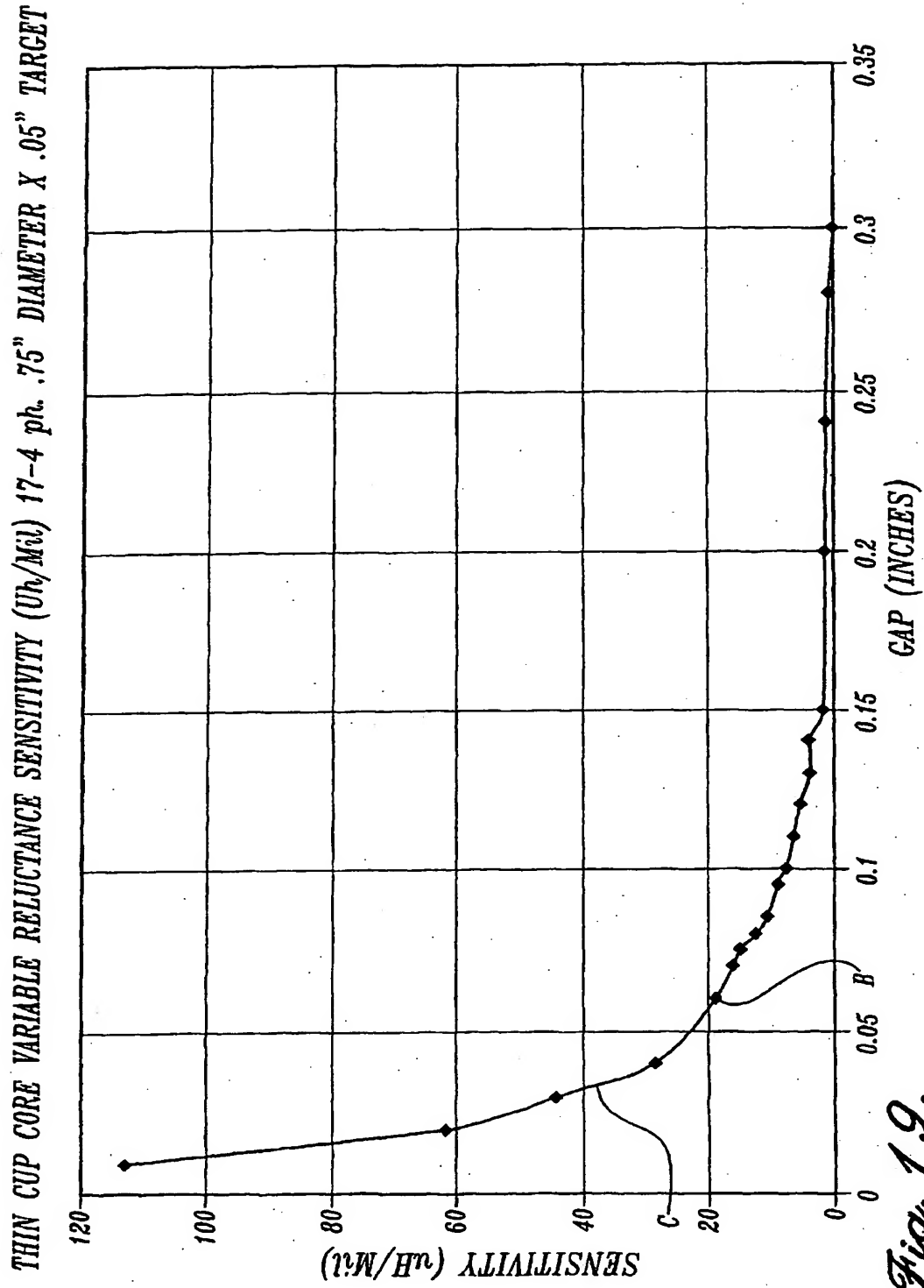


Fig. 19.